

**A STUDY OF DIGITAL CONTROL DESIGN METHODS**

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A STUDY OF DIGITAL  
CONTROL DESIGN METHODS

by

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## ABSTRACT

The development of microelectronics has brought into being large capacity digital memories in a small package. In the foreseeable future even more advances can be seen in this trend. Therefore the use of digital computers in control systems will play an even larger role than today.

This work involves a fourth order system to simulate the control and dynamics of a missile. Proportional navigation is used as the guidance method. Studied are the effects of applying different controls which are considered best from a computer study and the effects of applying digital filtering methods. Although these studies were applied to a specific problem, an attempt is made to keep the discussion general in order that the methods may be considered for other problems.

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## LIST OF SYMBOLS

$\gamma$	Missile flight path angle
$k$	Navigation constant
LOS	Line-of-sight
$\sigma$	Line-of-sight angle
$\beta$	Difference between sigma and gamma
$V_m$	Speed of missile
$V_t$	Speed of target
$S$	Laplace operator
$R$	Range, missile to target
$\wedge$	Effective navigation constant
$X$	State vector
$U$	Control vector
$F$	System matrix
$D$	Control system matrix
$b$	Forward gains
$a$	Feedback gains
$B$	Feed forward gain vector
$\Phi$	Transition matrix
$\Delta$ -DEL	Distribution matrix
$J$	Cost function
$Q$	Weighting matrix
$r$	Weighting constant
$A^T$	Feedback vector
$f(x)$	Density function
$F(X)$	Density function matrix
$P$	Covariance error matrix

$Z$	Noisy observable vector
$H$	Observable matrix
$V$	Measurement noise vector
$R$	Covariance matrix of measurement noise
$\sigma_x$	Standard deviation
$L$	Loss function
$\nabla$	Gradient
$\hat{X}$	Best estimate vector based on past information
$X^*$	Best estimate vector based on present information and past prediction
$G$	Optimum gain matrix
$W$	Excitation noise vector
$Q$	Covariance matrix of excitation noise
$DI$	DINP-Deterministic input

## CHAPTER I

### INTRODUCTION

If it is desired to hit a target with a missile, some form of guidance must be employed. This guidance would be selected weighing the desired objectives and an estimate of the target capabilities against the amount of money and missile space available. As suggested in the introduction, the advances in computer size and capabilities is, and will in the future, continue to change the weighting of these factors. Thus in the foreseeable future it may be possible to design a model of the system which will be in sufficient detail to predict the response of the real system to a high degree of accuracy. Using the micro-computers, this model could then become a part of the control system in the missile. Such a control system might be described in the block diagram in Figure 1-1.

In Figure 1-1 the missile measures and reacts to a signal which depends on the type of guidance employed. Such a signal might depend on the rate of change in the missile's radar seeker head which is tracking the line of sight from the missile to target. The missile will react to this signal, producing through its dynamics a change in the direction of its velocity vector, or the missile will take some other action called for by the particular guidance law being used. The model receives the measured signals and considers the measurable states from the missile dynamics. Since all the states of the model are measurable and the digital model in itself generates relatively little noise, the model becomes a

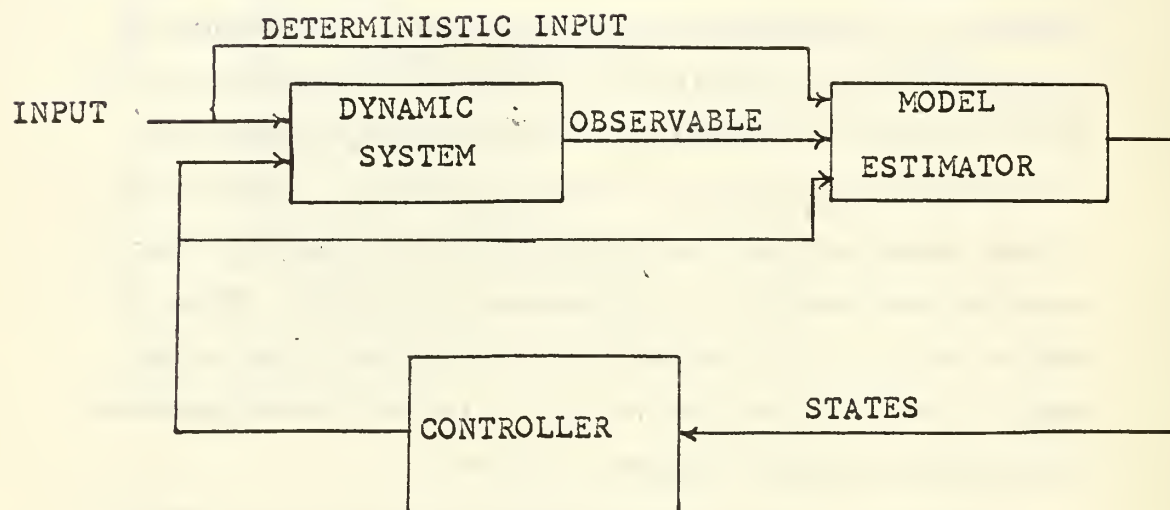


Figure 1-1. Block Diagram of a Dynamic System.



state predictor or estimator.

Since all the states of the model are available, a control law considering all the states can now be designed. This control law is applied in the controller to guide the missile.

If the desired objectives of the system can justify the above approach, the system performance of the modified system should be an improvement over most conventional guidance systems.

## CHAPTER II

### PROPORTIONAL NAVIGATION

Adler in [9] defined proportional navigation as,

A course in which the rate of change of missile heading is directly proportional to the rate of rotation of the line-of-sight from the missile to the target.

$$\dot{\gamma} = K \dot{\phi} \quad (1)$$

where

$\dot{\gamma}$  is the angular rate of change of the missile velocity vector.

$\dot{\phi}$  is the angular rate of change of the line-of-sight.

K is a constant, typically between three and five.

To gain a better understanding of proportional navigation, some of the simpler forms of line-of-sight guidance will be examined. Pursuit course (sometimes called pure pursuit) always aims the missile directly at the target along the line-of-sight. This method will always end in a tail chase, even if the missile is launched head-on with the target. High missile accelerations are required. It can be shown from the equations of motion that if the missile to target speed ratio exceeds two, the final missile turning rate will approach infinity. Thus pursuit course guidance may not be very satisfactory although it is very simple to implement.

The next step is to lead the line-of-sight by an angle which is a function of the target velocity. This type is called constant bearing course, and is achieved by aligning the relative missile to target velocity vector with the line-of-sight. That is to say the line-of-sight maintains a constant direction in space. It can be shown that this method can

cause a missile to follow a target to a collision even if the target is maneuvering. This method however requires an instantaneous correction to each change in the line-of-sight.

Consider the constant bearing trajectory shown in Figure 2-1. In the figure the line-of-sight is shown for several samples made by the radar. As long as the missile remains on the collision course, the angular rate of change of the line-of-sight will remain zero and no control action is required. Any rotation of the line-of-sight, indicating a departure from the collision course will be detected by the missile's radar. The missile using proportional navigation will turn at a rate proportional to this rotation in a direction to reduce the line-of-sight rate and return to a constant bearing collision course.

In the Figure 2-2 above, the lead angle  $\beta$  is defined:

$$\beta = \sigma - \gamma \quad (2)$$

This angle ( $\beta$ ) is independent of any reference used to define  $\sigma$  and  $\gamma$ . If, as in the discussion above, we could achieve a constant bearing course,  $\beta$  would remain a constant, and therefore  $\dot{\beta}$  would remain zero.

Thus for a constant bearing course,

$$\dot{\beta} = \dot{\sigma} - \dot{\gamma} = 0 \quad (3)$$

Since the missile cannot react instantaneously,  $\dot{\beta}$  is not always zero. Thus for any instant of time (1) may be written as,

$$K' \dot{\sigma} = \dot{\beta} + \dot{\gamma} \quad (4)$$

If  $\dot{\beta}$  is equal to zero, the missile is on a constant bearing collision course. Therefore the object of the control system

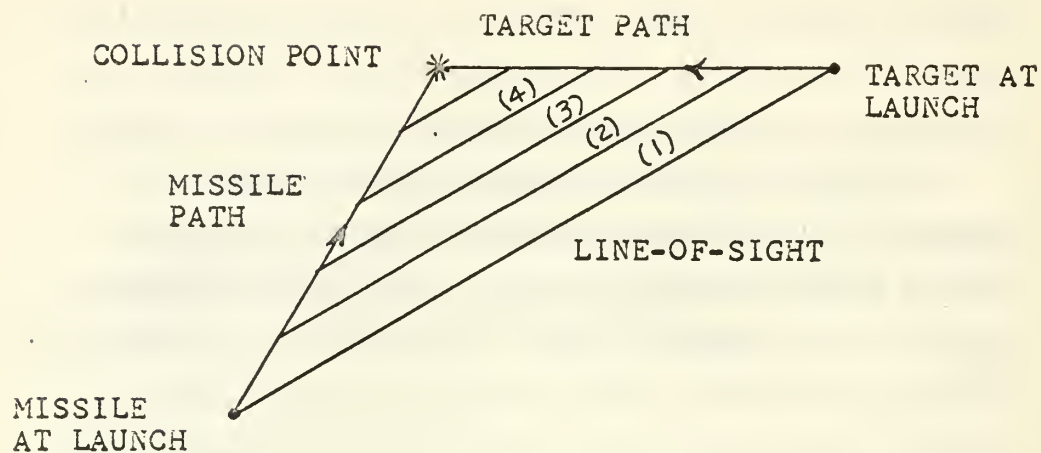


Figure 2-1. Constant Bearing Trajectory.

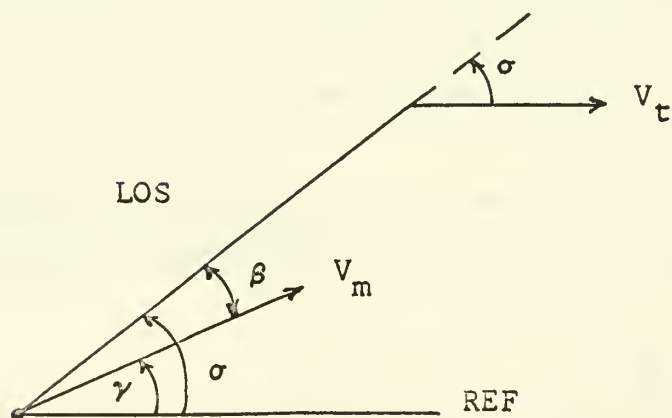


Figure 2-2. Proportional Navigation Geometry.

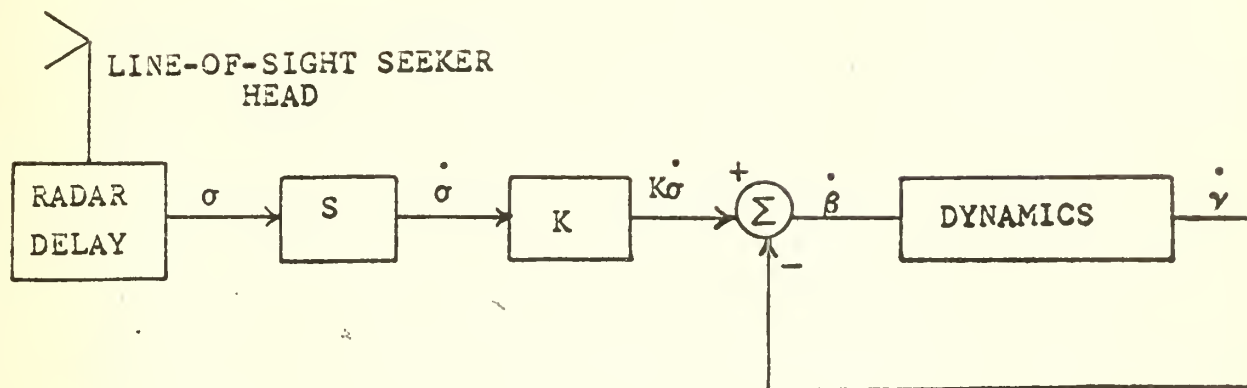


Figure 2-3. Missile Guidance Inter Loop.

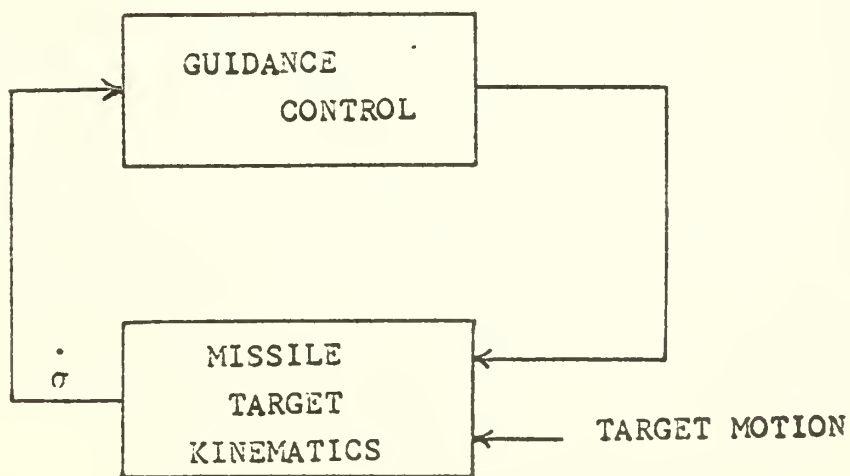


Figure 2-4. Missile Guidance Outer Loop.

in proportional navigation is to minimize  $\dot{\beta}$  and if  $\dot{\sigma}$  becomes a constant or zero to drive  $\dot{\beta}$  to zero.

### Guidance and Control

A typical homing missile inter guidance loop is shown in Figure 2-3. The following discussion will be limited to only coplanar motion of the missile and target. A constant missile and target speed is also assumed throughout the rest of this paper.

In Figure 2-3, the radar tracks the target using a servo loop to keep the antenna on the line-of-sight. A delayed signal which is a measure of  $\sigma$ , is obtained from the radar system. A voltage which is proportional to the rate of change of this signal is obtained. This voltage is compared with the output of the dynamic system  $\dot{\gamma}$ , and the error signal is obtained. This error signal is sent either to the hydraulic system to rotate the control surfaces or to a hydraulic/valve system which controls side thrust jets, depending on the type of missile being used.

### Kinematics

As might be suggested by the name inter loop, there is also an outer loop as shown in Figure 2-4. In the Figure, the guidance and control block is shown as in Figure 2-3. The effect of  $\dot{\gamma}$  on the line-of-sight and the effect of the target motion on the line-of-sight are represented in the missile-target kinematics block.

This outer loop is not as accessible to measurement and control, but the understanding of its effects is necessary in order to perform a simulation of the entire system. From

the geometry of Figure 2-2, the following equations may be written:

$$\dot{R} = V_t \cos(\sigma) - V_m \cos(\beta) \quad (5)$$

$$R\dot{\sigma} = -V_t \sin(\sigma) + V_m \sin(\beta) \quad (6)$$

where

$V_t$  = Target speed (assumed Constant)

$V_m$  = Missile speed (assumed Constant)

$\beta = \sigma - \gamma$

$R$  = the line-of-sight distance

$\dot{R}$  = the rate of change of the line-of-sight.

Then equations (5) and (6) may be rewritten:

$$\dot{R} = V_t \cos(\sigma) - V_m \cos(\sigma - \gamma) \quad (7)$$

$$R\dot{\sigma} = -V_t \sin(\sigma) + V_m \sin(\sigma - \gamma) \quad (8)$$

Differentiating (8) with respect to time:

$$\begin{aligned} \dot{R}\dot{\sigma} + R\ddot{\sigma} &= -V_t \cos(\sigma) \dot{\sigma} + V_m \cos(\sigma - \gamma)(\dot{\sigma} - \dot{\gamma}) \\ &= -\dot{R}\dot{\sigma} - V_m \cos(\sigma - \gamma) \dot{\gamma} \end{aligned} \quad (9)$$

Therefore

$$2\dot{R}\dot{\sigma} + R\ddot{\sigma} = -V_m \cos(\sigma - \gamma) \dot{\gamma} \quad (10)$$

let

$$\dot{R} = -R/T$$

and

$$V_r = \dot{R}$$

where  $T$  is the time to go to the target. Then equation (10)

may be represented by:

$$(-2R/T + RS) \dot{\sigma} = -V_m \cos(\sigma - \gamma) \dot{\gamma} \quad (11)$$

thus

$$\dot{\sigma}/\dot{\gamma} = \frac{-V_m \cos(\sigma - \gamma)}{R/T (TS - 2)} \quad (12)$$

Where  $\frac{V_m \cos(\sigma - \gamma)}{R/T}$  is called the effective navigation constant.

$R/T$

Since  $V_m$  is constant and variations in  $\cos(\sigma - \gamma)$  and  $V_r$  are small, this term is assumed constant and values of four to six are considered best.



# CHAPTER III

## FILTER AND CONTROL

### Plant Description

A linear, time-invariant dynamic system is described in the flow graph, Figure 3-1.

The transfer function of Figure 3-1 may be stated:

$$\frac{X_{out}(s)}{X_{in}(s)} = \frac{b_n s^{n-1} + \dots + b_2 s + b_1}{s^n + a_n s^{n-1} + \dots + a_2 s + a_1} \quad (1)$$

Equation (1) may be written in one differential equation using matrix notation.

$$\dot{X} = F X + D U, \quad C = B X \quad (2)$$

Where

X is the state vector (n x 1)

U is a scalar of the system inputs and controls

F is a matrix of constants. For the system described in Figure 3-1, F is defined in equation (3).

$$F = \begin{bmatrix} 0 & 1 & 0 & \dots & \dots & 0 \\ 0 & 0 & 1 & \dots & \dots & 0 \\ \dots & \dots & \dots & \dots & \dots & \dots \\ 0 & 0 & 0 & \dots & 1 & 0 \\ 0 & 0 & 0 & \dots & 0 & 1 \\ -a_1 & -a_2 & \dots & \dots & \dots & -a_n \end{bmatrix} \quad (3)$$

D is a matrix of constants (n x 1) described in equation (4) for the system in Figure 3-1.

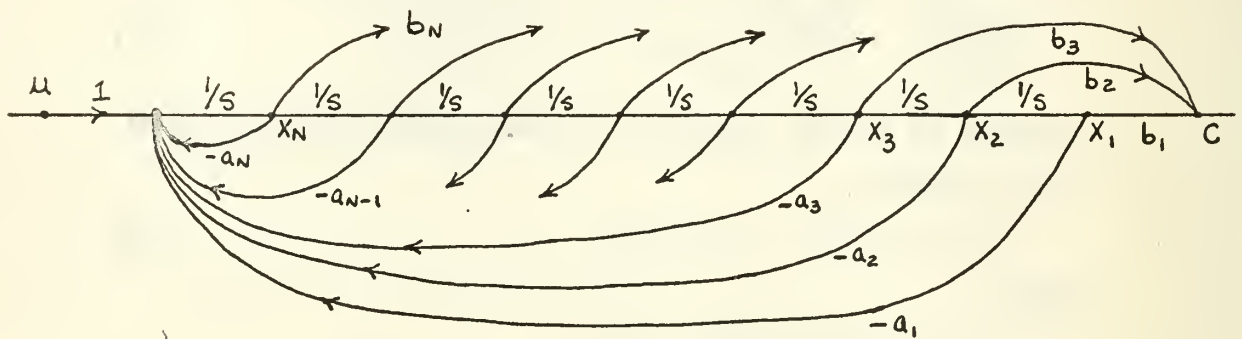


Figure 3-1. Flow Diagram of the system.

$$D = \begin{bmatrix} 0 \\ 0 \\ . \\ 0 \\ 1 \end{bmatrix} \quad (4)$$

B is an (1 x n) row vector, described in equation (5) for the system described in Figure 3-1.

$$B = [b_1 \ b_2 \ . \ . \ . \ b_n] \quad (5)$$

The solution to (2) is given by:

$$X(t) = \Phi(t - t_0) X(t_0) + \int_{t_0}^t \Phi(t - t_1) D dt_1 U(t_0)^1 \quad (6)$$

Where

$$\Phi(t - t_0) = \mathcal{L}^{-1} (SI - F)^{-1}$$

Solving the differential equation (2) for the discrete solution,

$$X(k + 1) = \Phi X(k) + DEL U(k) \quad (7)$$

Where

$$\Phi = e^{F(t - t_0)} \quad (8)$$

$$DEL = \int_{t_0}^t e^{F(t - t_1)} D dt_1 \quad (9)$$

Note that  $k(t - t_0)$  is represented by  $k$ .

Titus, in reference [10] developed a digital computer program called PHIDEL. This program provides a solution to equations (8) and (9) and will be used as a subroutine to obtain  $\Phi$  and DEL. A listing of the PHIDEL program is provided in Appendix one.

#### Plant Control

It is desired to design a set of feedback coefficients to control the plant in accordance with a selected performance

<sup>1</sup>  $U(t)$  is held constant over the interval  $(t - t_0)$  and is equal to  $U(t_0)$ .

index. This set of coefficients will modify the plant states and in effect will cause a movement of the Z-plane poles. This effect must be weighed against the feedback gains derived for the desired performance index.

Let  $J(N)$  be defined as the performance index of a discrete sample-data system which will be minimized with respect to  $U(K)$ , the control for the plant.

$$J(N) = \min_{U(K)} \sum_{K=M}^N [X^t(K) Q X(K) + r U^2(K-1)] \quad (10)$$

$Q$  is a  $(n \times n)$  positive-definite symmetric constant matrix, and  $R$  is a positive scalar constant.

The principle of optimality states that any portion of an optimal trajectory is also an optimal trajectory. Therefore equation (1) may be rewritten:

$$J(N) = \min_{U(N)} [X^t(N) Q X(N) + r U^2(N-1) + J(N-1)] \quad (11)$$

If the gradient of  $J(N)$  is taken with respect to  $U(N-1)$  and set equal to zero, then an optimal control,  $U^O(N-1)$  may be determined. It is noted that  $J(N-1)$  is not a function of  $U(N-1)$ .

Using the above arguments, Titus developed the following algorithms:

$$A^t(k+1) = \frac{-\Delta^t P(k) \Phi}{\Delta^t P(k) \Delta + r} \quad (12)$$

$$P(k) = \Psi^t(k) P(k-1) \Psi(k) + Q + r A(k) A^t(k) \quad (13)$$

$$\Psi(k) = \Phi + \Delta A^t(k) \quad (14)$$

Using the recursive relations of (12), (13) and (14), Titus [10] developed program OPTCON. This method is also discussed in references [3] and [4] by Titus, Strum and Demetry, and

in reference [6] by Ogden. A fortran listing of the program may be found in Appendix one.

### Digital Filter

In the control discussion, the assumption was made that all the states of the dynamic system are observable states. This condition is certainly not always true and often the observable states may be measured only at the cost of some ambiguity due to the measurement noise. The inputs to the system such as the radar seeker discussed in Chapter Two will often be received in a noisy environment.

Kalman in references [1] and [2] discussed these problems and presented the theory for the desired filter. Schmidt [5]; Titus, Demetry and Strum [4] and Jardine [7] have discussed this problem and developed methods of implementing this problem on the digital computer. In an effort to maintain clarity, some of these developments will be presented.

The digital filter will provide a best estimate of all the states by weighing the past information with the present observable states. This weighting is performed with the knowledge of the environment (excitation) and the measurement noise. Although in many cases the noise is very difficult to describe, the assumption that white noise is present is in general true. Thus if white noise can be discriminated, the integrity of the measured signals will be improved.

### Filter Design

For a single variable, the density function  $f(x)$  for a gaussian distribution is given by:

$$f(x) = \frac{1}{(2\pi)^{\frac{1}{2}} \sigma} e^{-\frac{1}{2\sigma^2}(x - u)^2} \quad (15)$$

where

$$\int g(x)f(x)dx = E[ g(x) ] \quad (16)$$

where E implies expected value,

and

$$\int f(x)dx = 1 \quad (17)$$

Assume that the systems measurement and excitation noise are white noise, where white noise has a gaussian distribution and is spread uniformly over all frequencies.

Noting that the input,  $U(k)$  to the plant is independent of  $U(k - 1)$ ,  $X(k)$  is independent of  $X(k - 1)$  and using the joint probability property of random independent samples, a density function for the state system may be written:

$$F(X) = \frac{1}{(2\pi)^{n/2} P^{\frac{1}{2}}} e^{-\frac{1}{2}[X - \hat{X}]^t P^{-1} [X - \hat{X}]} \quad (18)$$

where  $\hat{X}(k)$  is the best estimate of the states based on past information.

$$Z(k - 1) = H X(k - 1) + V(k - 1) \quad (19)$$

$Z$  is the noisy observable matrix, and  $V$  is the measurement noise vector defined by:

$$E[V] = 0 \quad (20)$$

$$E[VV^t] = R \quad (21)$$

$R$  is the covariance matrix of the measurement noise and  $P$  is the covariance matrix of the error.  $P$  is a symmetric matrix, ( $P_{ij} = P_{ji}$ ). The diagonal terms of  $P$  are equal to the variance of each state ( $\sigma^2_{x_i}$ ) and the off-diagonal terms are equal to

correlation between the states,

$$(E[x_i \cdot x_j] - \hat{x}_i \cdot \hat{x}_j).$$

$$P = E[ [X - \hat{X}] \cdot [X - \hat{X}]^t ] \quad (22)$$

The expected value of the error is defined as the loss function:

$$L = \int (X - \hat{X})^t (X - \hat{X}) F(X/Z, \hat{X}) dX \quad (23)$$

Taking the gradient of equation (23) with respect to  $\hat{X}$ ;

$$\nabla_{\hat{X}} L = \int 2X F(X/Z, \hat{X}) dX - 2\hat{X} \int F(X/Z, \hat{X}) dX \quad (24)$$

Applying equations (16) and (17) and setting the result equal to zero

$$\nabla_{\hat{X}} L = 2 E [X/Z, \hat{X}] - 2\hat{X} = 0$$

Thus:

$$X^* = \text{Max}(\hat{X}) = E[X/Z, \hat{X}] \quad (25)$$

$X^*$  is the best estimate of the states given the present noisy observable and the past prediction of the states.

### Filter Equations

There are two methods of finding the recursive relations for the filter program. Method one assumes the random variables are gaussian and makes use of Bayes equation to derive an expression for equation (25). Method two assumes a linear filter, selects an algorithm for equation (25) and proves that this selection provides the best values for  $X^*$ .

### Method One

The covariance matrix of the observable error may be written:

$$P_Z = E[(Z - \hat{Z})(Z - \hat{Z})^t] \quad (26)$$

Combining equations (19) and (26),

$$\begin{aligned} P_Z &= E[(HX + V - H\hat{X})(HX + V - H\hat{X})^t] \\ &= H E[(X - \hat{X})(X - \hat{X})^t] + E[VV^t] \end{aligned}$$

Using equations (20), (21) and (22),

$$P_Z = HPH^t + R \quad (27)$$



In order to find an expression for  $X^*$ , Bayes formula is applied to equation (25).

$$X^* = F(X/Z, \hat{X}) = \frac{F(Z, \hat{X}/X) F(X)}{F(Z, \hat{X})} \quad (28)$$

Since  $Z(k)$  is independent of  $\hat{X}(k)$ , equation (28) may be written:

$$F(X/Z, \hat{X}) = \frac{F(Z/X) F(\hat{X}/X) F(X)}{F(Z) F(\hat{X})} \quad (29)$$

Since  $F(\hat{X}/X) = \frac{F(X/\hat{X}) F(\hat{X})}{F(X)}$ , equation (29) becomes,

$$F(X/Z, \hat{X}) = \frac{F(Z/X) F(X/\hat{X})}{F(Z)} \quad (30)$$

Since  $X(k)$  is independent of  $\hat{X}(k)$ , (30) becomes,

$$F(X/Z, \hat{X}) = \frac{F(Z/X) F(X)}{F(Z)} \quad (31)$$

Following the form in equation (18),  $F(Z)$  and  $F(Z/X)$  are defined:

$$F(Z) = \frac{1}{(2\pi)^{n/2} |P_Z|^{\frac{1}{2}}} e^{-\frac{1}{2}(Z - \hat{Z})^t P_Z^{-1} (Z - \hat{Z})} \quad (32)$$

$$F(Z/X) = F(V) = \frac{1}{(2\pi)^{n/2} |R|^{\frac{1}{2}}} e^{-\frac{1}{2}(V^t R^{-1} V)} \quad (33)$$

Combining equations (18), (31) and (33),

$$F(X/Z, \hat{X}) = A e^{-\frac{1}{2} B}$$

Where

$$A = \frac{(HPH^t + R)^{\frac{1}{2}}}{(2\pi)^{n/2} |R|^{\frac{1}{2}} |P|^{\frac{1}{2}}}$$

and

$$B = V^t R^{-1} V - (X - \hat{X})^t P^{-1} (X - \hat{X}) + (Z - \hat{Z})^t (HPH^t + R)^{-1} (Z - \hat{Z})$$

Setting the gradient of  $B$  with respect to  $X$  equal to zero.

$$\nabla_X B = \frac{1}{2}(2(X - \hat{X})^t P^{-1} - 2(Z - \hat{Z})^t (HPH^t + R)^{-1} \nabla_X (Z - \hat{Z})) = 0$$

since

$$\nabla_X (Z - \hat{Z}) = \nabla_X (HX + V) = H, \text{ the algorithm, equation (35)}$$



may be written.

$$X^* = \hat{X} + PH^t(HPH^t + R)^{-1}(Z - \hat{Z}) \quad (35)$$

Let the filter gain matrix  $G$  be defined.

$$G = PH^t(HPH^t + R)^{-1} \quad (36)$$

Then the algorithm, equation (35) may be written:

$$X^* = \hat{X} + G(Z - \hat{Z}) \quad (37)$$

### Method Two

An alternate method of deriving the recursive relation for the gain matrix assumes a linear filter. The trace of the covariance matrix is given by:

$$L = E[(X - \hat{X})^t(X - \hat{X})] \quad (38)$$

It will be shown that if  $L$  is minimized with respect to the gain, then the gain will be given by equation (36).

Substituting equation (37) into equation (38),

$$L = E[(X - \hat{X})(X - \hat{X})^t] - E[(X - \hat{X})(Z - \hat{Z})^t G^t] - E[G(Z - \hat{Z})(X - \hat{X})^t] + E[G(Z - \hat{Z})(Z - \hat{Z})^t G^t] \quad (39)$$

Since  $Z = HX + V$

Then  $\hat{Z} = E[HX + V] = H\hat{X}$

Assuming that  $E[(X - \hat{X})V^t]$  is equal to zero, equation (39) may be written:

$$L = E[(X - \hat{X})(X - \hat{X})^t] - E[(X - \hat{X})(X - \hat{X})^t]H^t G^t + GE[VV^t] - GH E[(X - \hat{X})(X - \hat{X})^t] + GHE[(X - \hat{X})(X - \hat{X})^t H^t G^t] \quad (40)$$

Substituting equations (21) and (22) into equation (40),

$$L = P - PH^t G^t - GHP + GHPH^t G^t + GRG^t \quad (41)$$

Taking the gradient of  $L$  with respect to  $G$  and solving for  $G$ .

$$G = PH^t(HPH^t + R)^{-1}$$

### Filter Programs

Jardine, Titus, Demetry and Strum have designed programs to calculate the filter gains and the covariance matrix of error.

Such a program, (Program Filter) is listed in Appendix one.

## CHAPTER IV

### DIGITAL SIMULATION

If a digital filter can be obtained, then a method must be developed to evaluate this system. This chapter will describe the simulation of the missile tracking system, the digital predictor, the control, and the kinematics. The results of this simulation for a particular missile will be discussed and trajectories from computer runs will be presented in Chapter Five.

#### Missile Guidance

Figure 4-1 is a block diagram of the digital simulation. As described in previous chapters, the missile system tracks the target, obtaining an input for the missile guidance. This signal is proportional to the angular rate of change of the line-of-sight angle. In this simulation it is assumed that white noise is added to this signal.

The details of the missile guidance simulation are described in Appendix Two. This portion of the simulation describes the tracking, control and dynamics of the missile as a transfer function relating the line-of-sight angular rate to the missile flight path angular rate. This transfer function is then formed into an F and D matrix as described in Chapter Three. Program Phidel is employed to obtain the  $\Phi$  and  $\Delta$  matrixes for the state difference equation.

The output of the missile guidance ( $\dot{\gamma}$ ) is considered the observable for the predictor. Gaussian measurement noise with standard deviation ( $\sigma_{\gamma}$ ) is added to the observable. The output ( $\dot{\gamma}$ ) is also an input to the kinematics. Figure 4-2

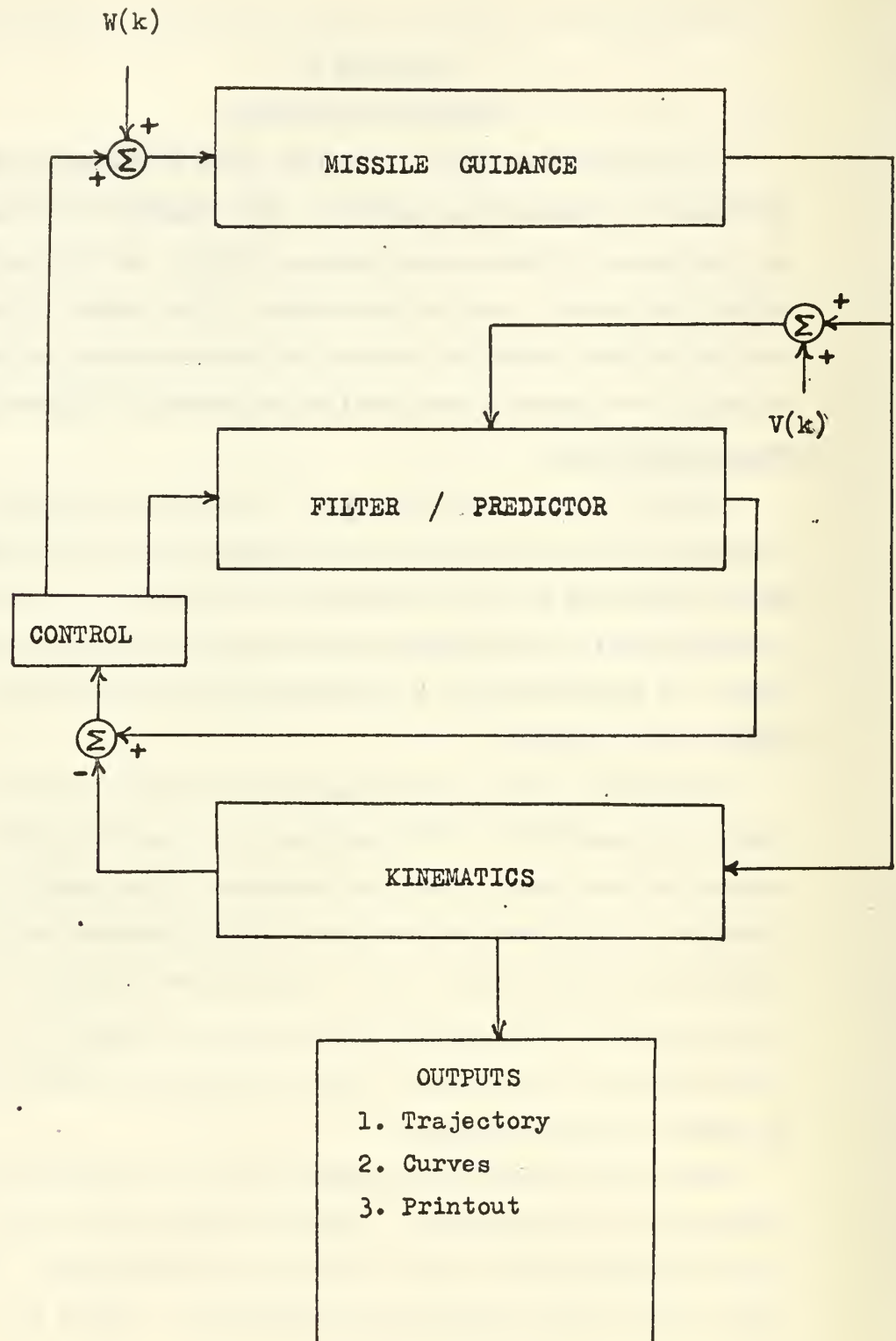


Figure 4-1. Block Diagram of Missile Simulation.

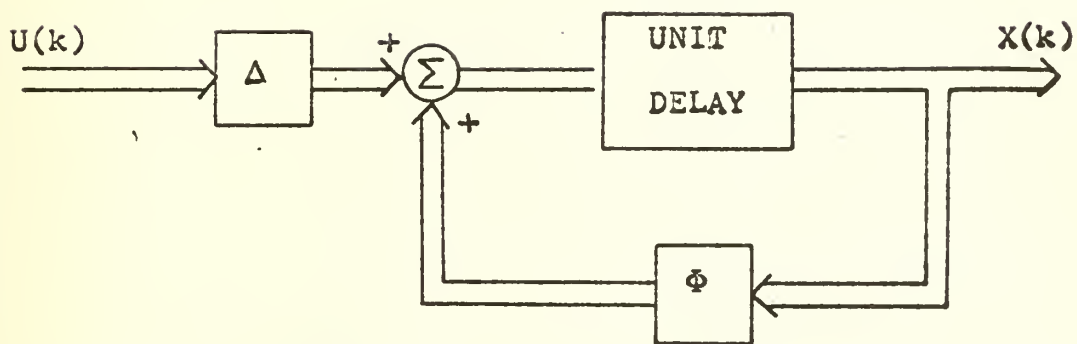


Figure 4-2. Discrete Flow Graph of the Plant.

describes the digital simulation of the guidance. The following fortran listing updates the discrete difference equation as demonstrated in Figure 4-2.

```
C  THIS SECTION UPDATES THE STATE VECTOR X
    CALL RNDEV(NUNIF,DEV)
    W=SIGW*DEV
    CALL PROD(PHI,X,KN,KN,1,TEMP1)
    DO 803 I = 1,KN
803  TEMP2(I,1) = W*DEL(I,1)
    CALL ADD(XS,DINP,KN,1,TELP)
    CALL PROD(AT,TELP,1,KN,1,TELP1)
    CALL PROD(DEL,TELP1,KN,1,1,TELP2)
    CALL ADD(TEMP1,TEMP2,KN,1,X)
    CALL ADD(X,TELP2,KN,1,X)
```

#### Digital filter-predictor

The digital filter is similar to the filter described in reference [4]. The gain matrix (G) is evaluated each sample instead of using the steady-state values of the gain. The discrete flow graph of the filter is shown in Figure 4-3.

One input to the filter is the noisy observable. This is the sum of the angular rate of the missile flight path ( $\dot{\gamma}$ ) and the measurement noise. This noise is assumed gaussian with mean zero and variance  $\sigma_v$ . This measurement on the missile could be made by use of rate gyros.

The other input to the filter is the deterministic input. Here this would be the angular rate of the line-of-sight ( $\dot{\sigma}$ ) and the best estimate of its derivatives. In the simulation

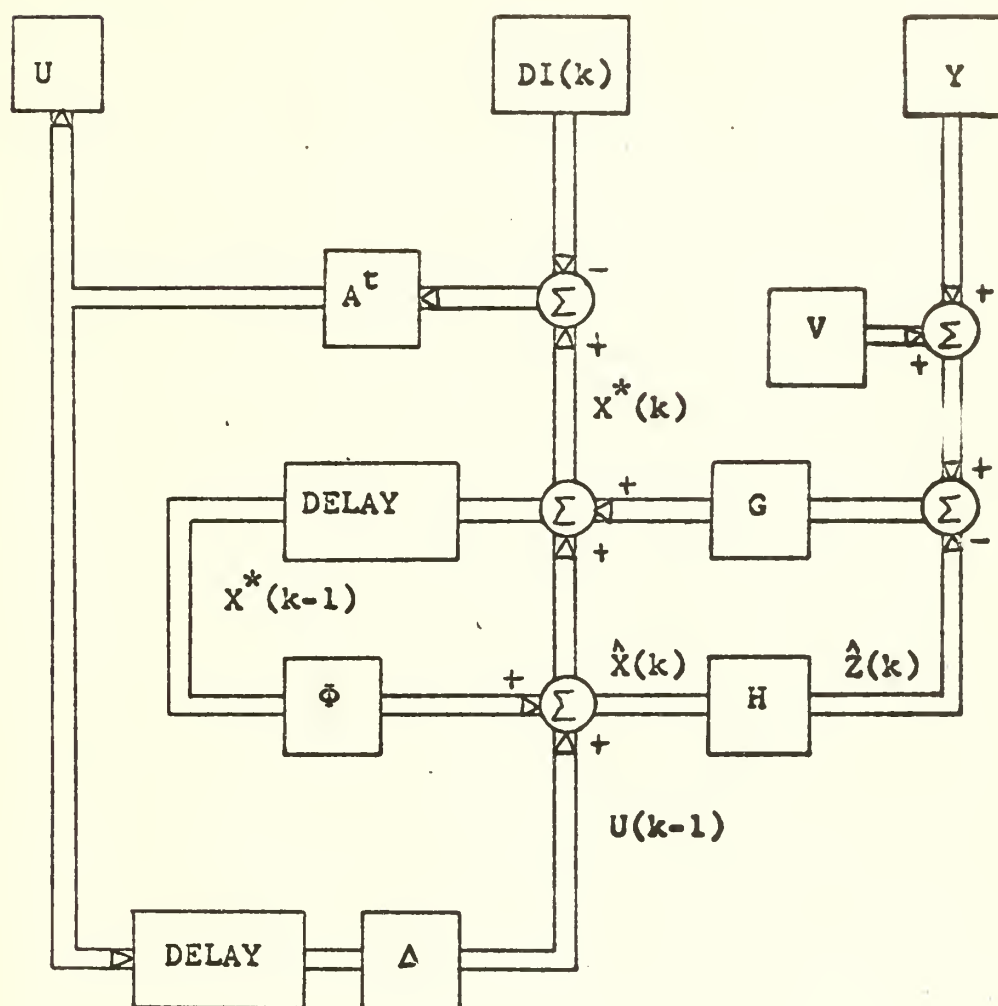


Figure 4-3. Discrete Flow Graph of the Filter/predictor



these are obtained from the kinematics. In the missile this signal would be measured by the tracking system. Note that the present value of the deterministic input  $DI(k)$  is used as the input to the plant while the past value of the input  $DI(k - 1)$  is used in the filter. The reasoning is that the filter is taking the present value of the observable  $Z(k)$  and therefore must use the past value of the deterministic input  $DI(k - 1)$  which caused the observable  $Z(k)$ .

The fortran statements for the filter are listed below.

```

C   THIS SECTION CALCULATES XS, THE BEST ESTIMATE
C   OF THE STATE VECTOR
      CALL PROD(H,X,KP,KN,1,Y)
      DO 10 I=1,KP
        CALL RNDEV(NUNIF,DEV)
10    V(I,1) = SIGV(I)*DEV
      CALL ADD(Y,V,KP,1,Z)
      CALL PROD(PHI,XS,KN,KN,1,TEMP1)
      DO 11 I = 1,KN
        DO 11 J = 1,KN
11    TEMP2(I,J) = -TEMP2(I,J)
      CALL PROD(TEMP2,TEMP1,KN,KN,1,TEMP3)
      CALL ADD(TEMP1,TEMP3,KN,1,TEMP3)
      CALL ADD(XS,DINP,KN,1,TELP)
      CALL PROD(AT,TELP,1,KN,1,TEMP1)
      CALL PROD(DEL,TEMP1,KN,1,1,TELP)
      CALL PROD(TEMP2,TELP,KN,KN,1,TELP1)
      CALL ADD(TELP,TELP1,KN,1,TELP1)
      CALL PROD(G,Z,KN,KP,1,TELP2)

```



```
CALL ADD(TEMP3,TELP1,KN,1,XS)
```

```
CALL ADD(XS,TELP2,KN,1,XS)
```

### The Kinematics

The kinematics combines the flight path angular rate of the missile, the missile speed (assumed constant) and the target's velocity vector to determine their effect on the line-of-sight angular rate ( $\dot{\sigma}$ ) and the range rate ( $\dot{R}$ ).

Figure 4-4 demonstrates the sign conventions used in this simulation. The trajectories which will be discussed later in Chapter Five use this same notation and sign convention.

Figure 4-5 demonstrates in block diagram form the kinematics. As noted in the figure, by-products of the kinematics are (1) the position of the missile and target, (2) the range and (3) the sign and magnitude of the range rate.

By addition of a few fortran statements, adjusting the target's velocity vector, the target can be maneuvered as a function of the missile trajectory in range (evasion) or on a predetermined course (attack).

The fortran statements for the kinematics are listed below.

```
C THIS SECTION DETERMINES THE EFFECT OF THE
```

```
C PLANT OF THE KINEMATICS
```

```
GAMDOT = X(1,1)
```

```
GAMMA = GAMMA+GAMDOT*DT
```

```
XMDOT = VM*COSF(GAMMA)
```

```
YMDOT = VM*SINF(GAMMA)
```

```
YRDOT = YTDOT-YMDOT
```

```
XRDOT = YTDOT-YMDOT
```

```
RDOT = ((YRDOT*SINF(SIGMA))+(XRDOT*COSF(SIGMA)))
```

```
RDSIG = ((YRDOT*COSF(SIGMA))-(XRDOT*SINF(SIGMA)))
```

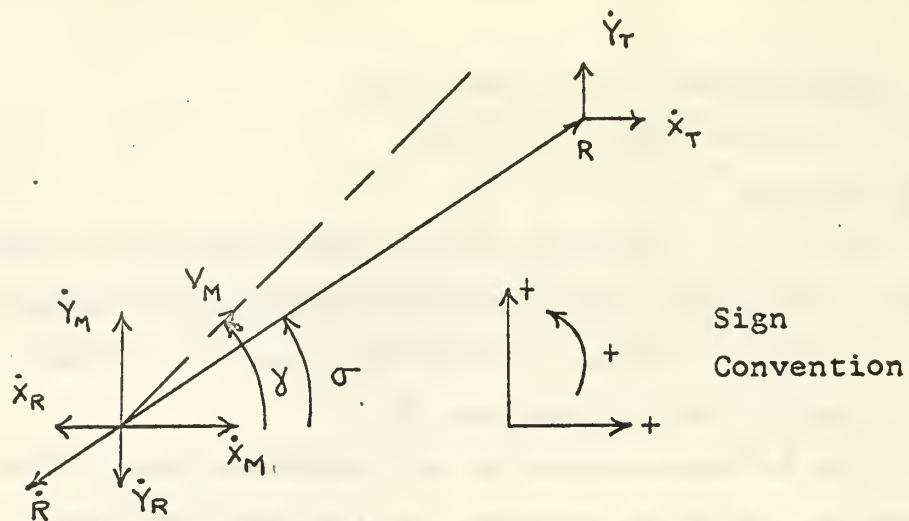


Figure 4-4. Geometry of the Kinematics.

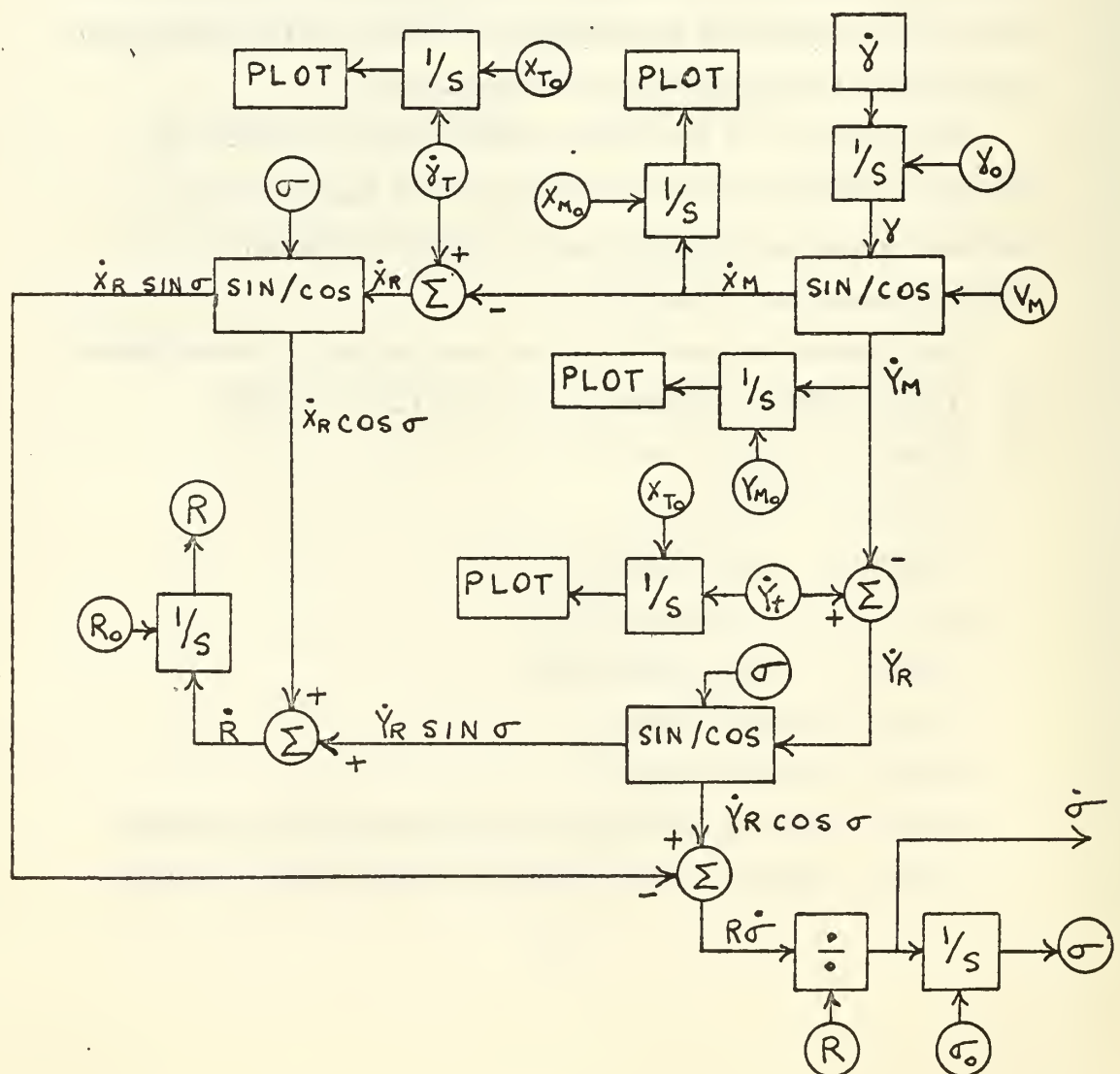


Figure 4-5. Block diagram of the Kinematics.

```

RLOS = RLOS+RDOT*DT
DSIG = RDSIG/RLOS
SIGMA = SIGMA+DSIG*DT
XMZ = XMZ+XMDOT*DT
YMZ = YMZ+YMDOT*DT
XTZ = XTZ+XTDOT*DT
YTZ = YTZ+YTDOT*DT

```

### The Control

In this simulation a control ( $A^T$ ) was selected through the use of program "OPCON" which minimizes the states  $X(k)$ , ie, "bang-bang control". Other forms of control are also available such as placing a limit of the fuel or energy expended, placing a limit on the amount of acceleration allowed, or placing a limit on the magnitude of the angle and angular rate that can be measured. These options are recommended for future study and would, of course, be necessary in making a more complete study of the missile systems.

For this simulation the weighting vector ( $A^t$ ) becomes a constant vector which is imposed on the difference between the best prediction of the states  $X^*(k)$ , and the deterministic input,  $DINP(k)$  to determine the control to be applied.

Figure 4-6 is a discrete flow graph of the entire simulation. The fortran listing of the entire program may be found in Appendix One.

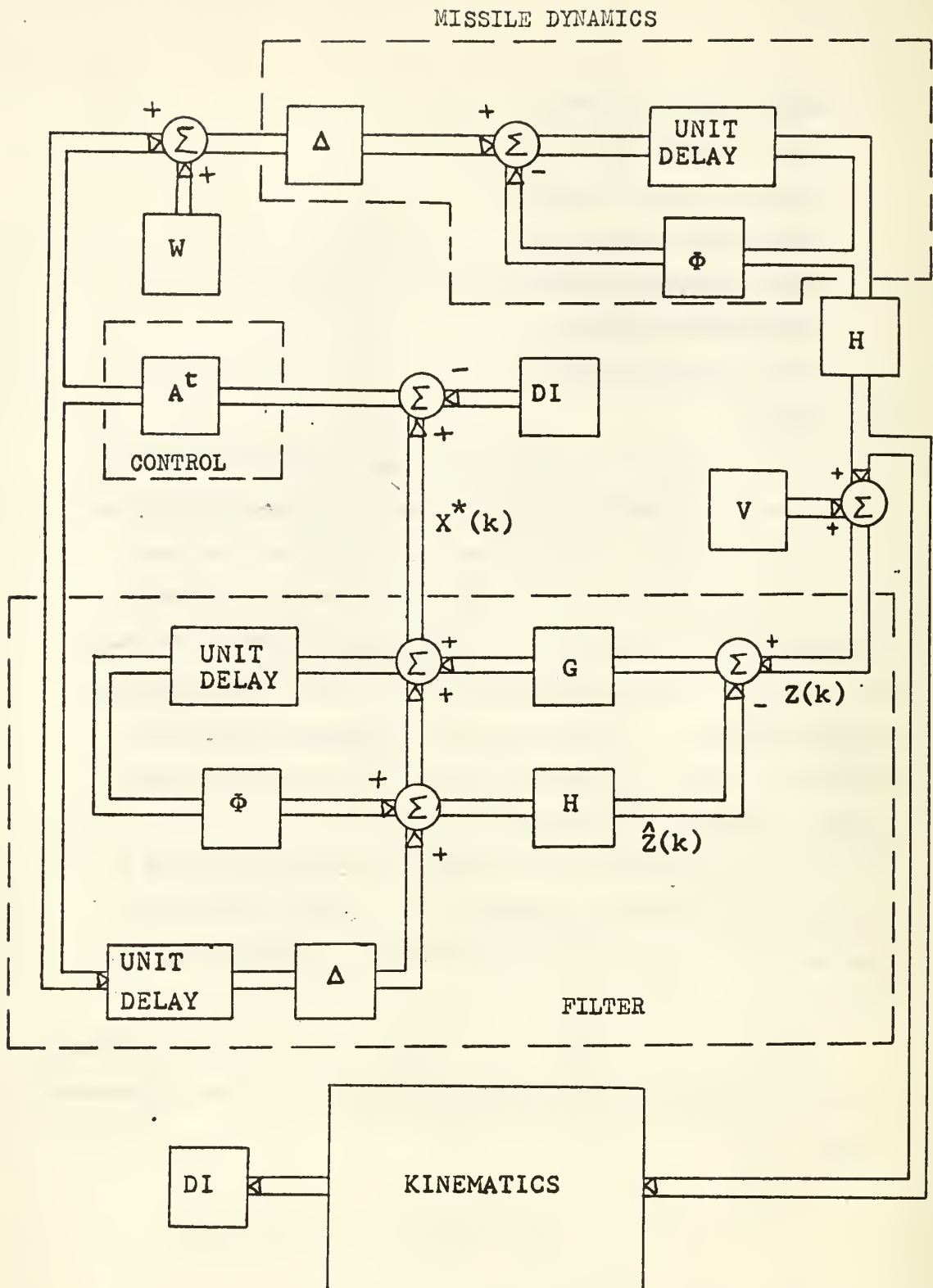


Figure 4-6. Discrete flow graph of missile simulation.

## CHAPTER V

### SIMULATION RESULTS

In making a study such as the evaluation of a missile guidance, it is quite difficult to decide which parameters to vary and which to hold constant. It is even more difficult to decide which curves hold the most meaning as a measure of success. Since the ultimate goal is to hit the target, trajectories and confirming print-out were used as a primary measure. Once a hit was obtained with a set of noise variances, the target trajectory was varied to see the effect on the missile. The noise was also varied to study the amount of noise that could be tolerated.

The measurement noise was found to be the most critical value. A standard deviation of measurement noise of 0.1 radians/sec was found to be the upper limit. Above this value the missile had some control, but the missile trajectories were far from desirable. Operation near the limit of measurement noise caused large ambiguities of the target information at the beginning of the flight. The target information improved as the range decreased, however, and in most cases the missile was able to capture the target.

Curves of the normal acceleration of the missile, the filter gains, the range, and the control versus time were considered and are shown in the results where these values appear to be critical or of interest.

This simulation assumed that the missile propulsion has already burned out and the missile is traveling at a constant velocity ( $V_m$ ). This simulation considers only the coplanar situation. The program could be easily expanded to two channels

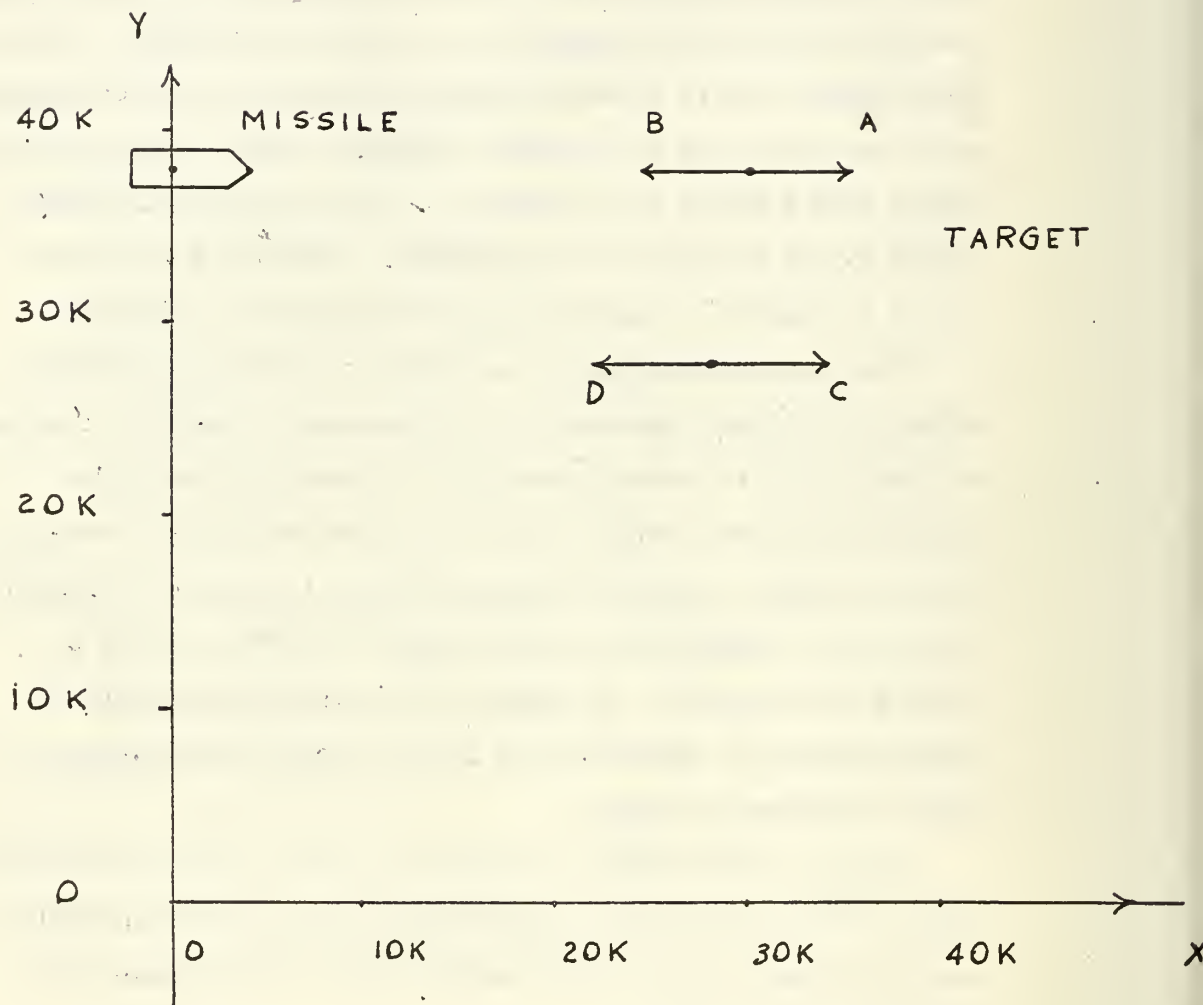


Figure 5-1 INITIAL CONDITION OF TARGET

Target velocity direction: A,B,C,D

Missile: Same initial position for all runs



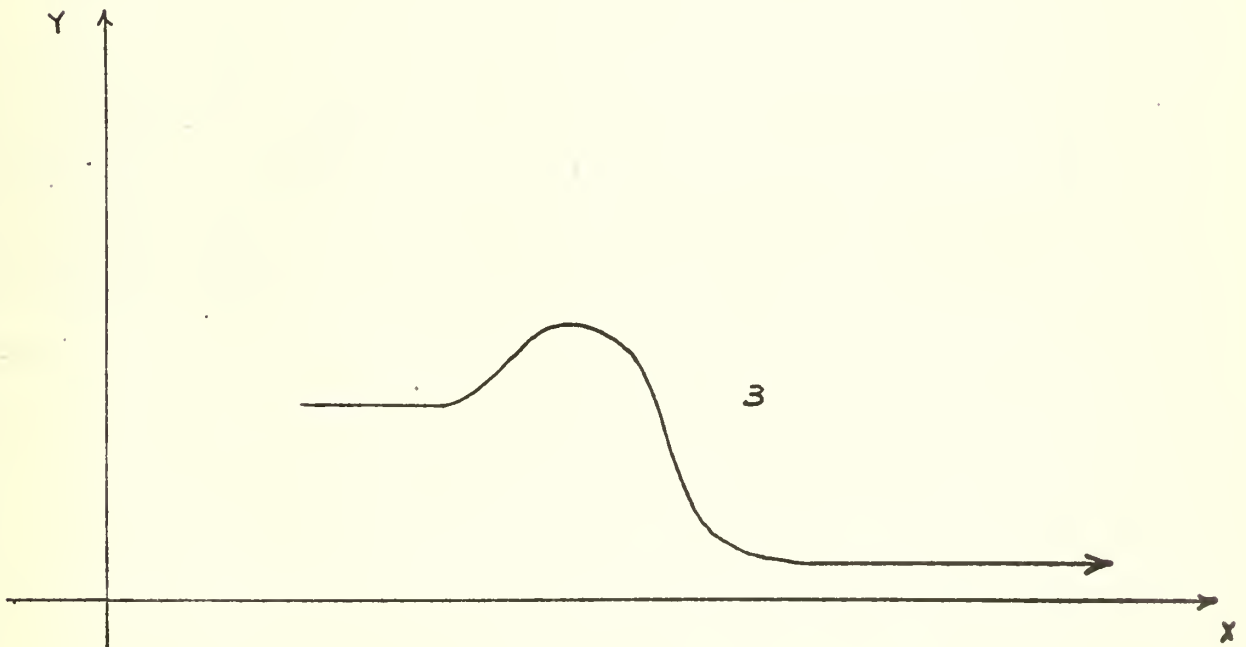
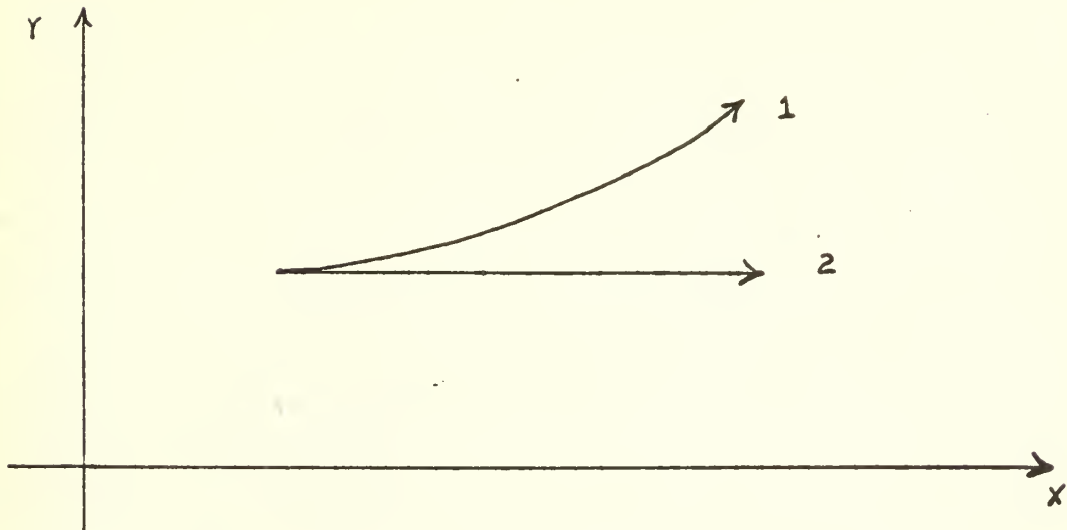


Figure 5-2

EVASION COURSES FOR TARGET  
TARGET TRAJECTORIES

Table 5-1

## INITIAL CONDITIONS

	A-1	B-1	C-1	D-1	
$Y_m$	3000 *	3000	3000	3000	
$X_m$	0	0	0	0	
$Y_m$	38000 #	38000	38000	38000	
R	30000 #	30000	30000	30000	
$X_t$	30000 #	30000	28300	28300	
$Y_t$	38000 #	38000	28000	28000	
$\dot{X}_t$	1000 *	-1000	1000	-1000	
$\dot{Y}_t$	0 *	0	0	0	
$\sigma$	0	0	-19.5°	-19.5°	
$\gamma$	0	0	-13.1°	-25.9°	
$\dot{R}$	2000 *	4000	2040	3930	

Velocity (Ft/sec) - \*

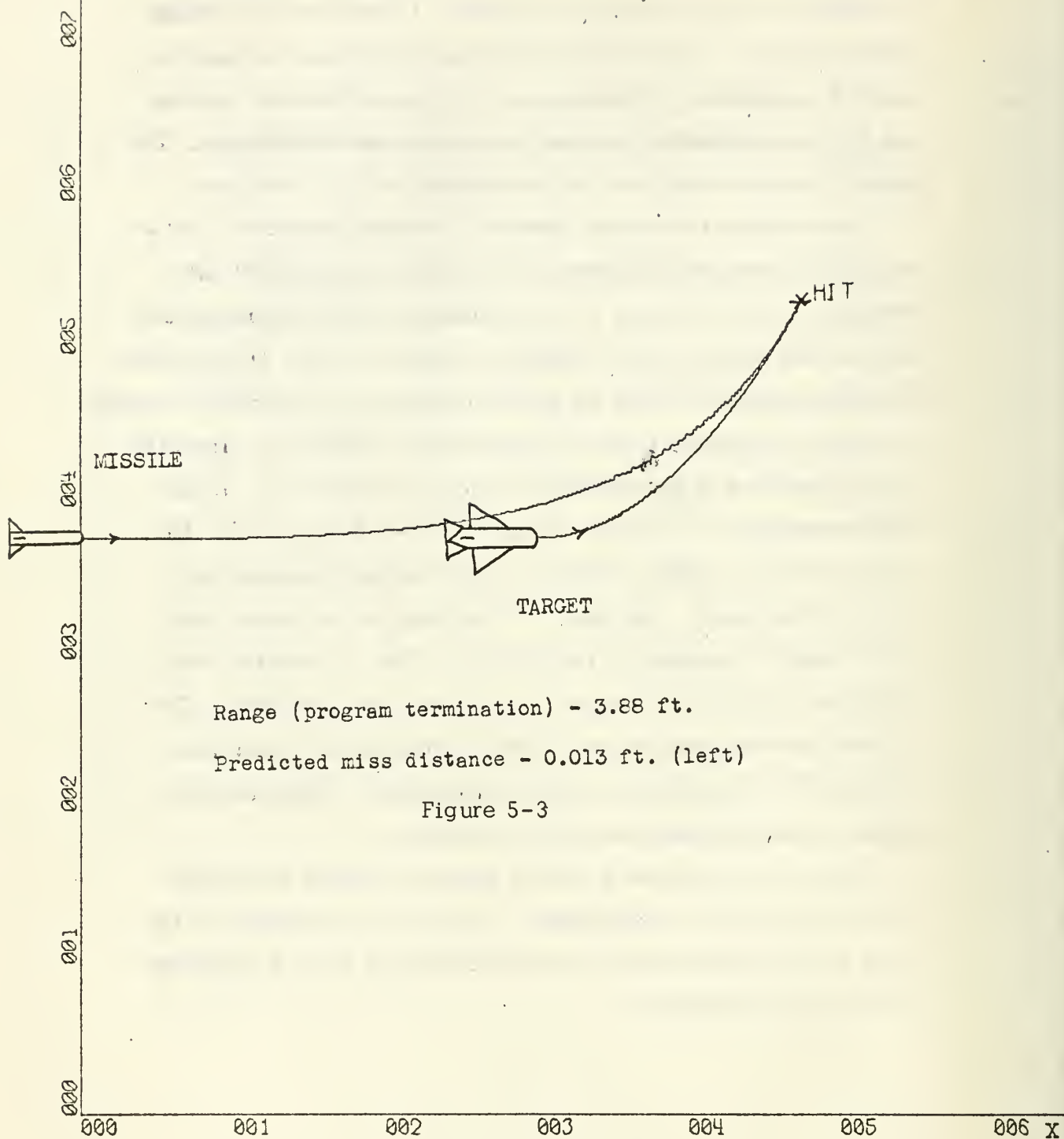
Position (Ft.) - #



and crosscoupling could be considered. The trajectories may be considered as yaw or pitch maneuvers. If they are considered pitch maneuvers, the effects of altitude variations and gravity must be considered. Otherwise it is assumed that the missile has the same dynamic reaction to a change in either plane. The gravity consideration was not considered in this simulation.

The target was made to under-go several maneuvers: (1) a turn, (2) a straight line course, and (3) a left/right/left turn (evasive course). Figure 5-1 is a graphic representation of the missile and target initial conditions where A, B, C, D represents the target velocity vector for the four cases. The numerical values of all the parameters involved are listed in Table 5-1. The different maneuvers of the target are shown in Figure 5-2. A particular computer run will be designated (A-1-2-0.1-0.1). The "A" implies the initial conditions of the target (position and velocity direction). The first "1" implies that the magnitude of the target's velocity is 1000 ft/sec. The "2" implies that the target is flying a straight line course (maneuver two). The last two numbers are the standard deviation of the excitation noise and the measurement noise respectively. Note that all angles in this program are given in radians.

Figure 5-3 to Figure 5-26 are presented below to display the filtered missile capabilities. Listed on each figure are the range at which the program was terminated ( $R < 100$  ft.) and the predicted miss distance.



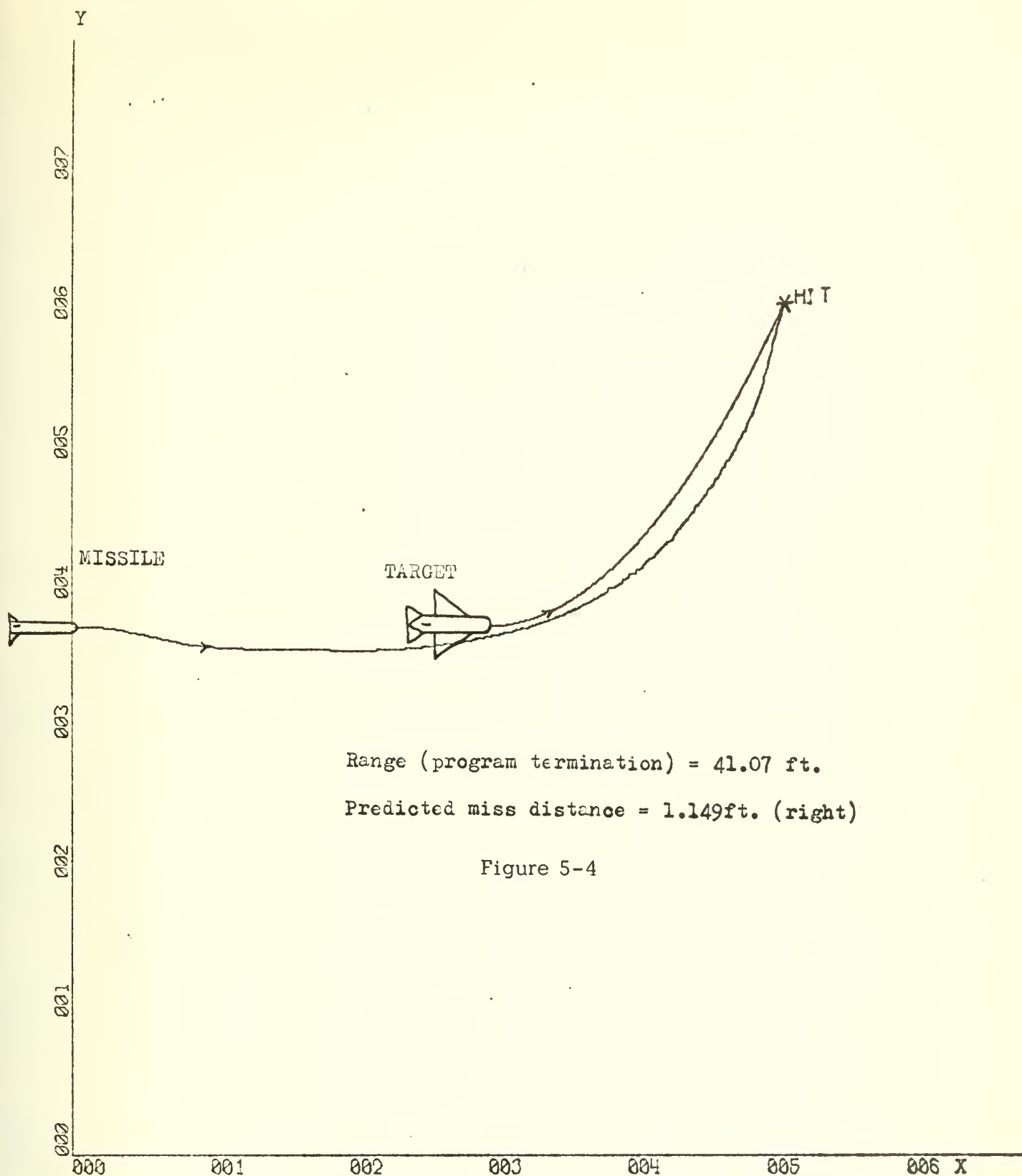
X-SCALE = 1.00E+04 UNITS/INCH.

(units - feet)

Y-SCALE = 1.00E+04 UNITS/INCH.

MISSILE ACTIVE GUIDANCE SIMULATION

A-1-1-0.01-0.01

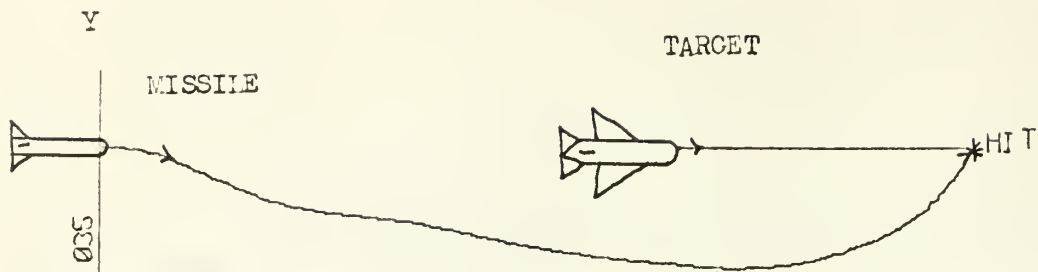


X-SCALE =  $1.00E+04$  UNITS/INCH. (units = feet)

Y-SCALE =  $1.00E+04$  UNITS/INCH.

SIMULATION OF GUIDED MISSILE/FILTER(STEELE)

A-1-1-0.1-0.1



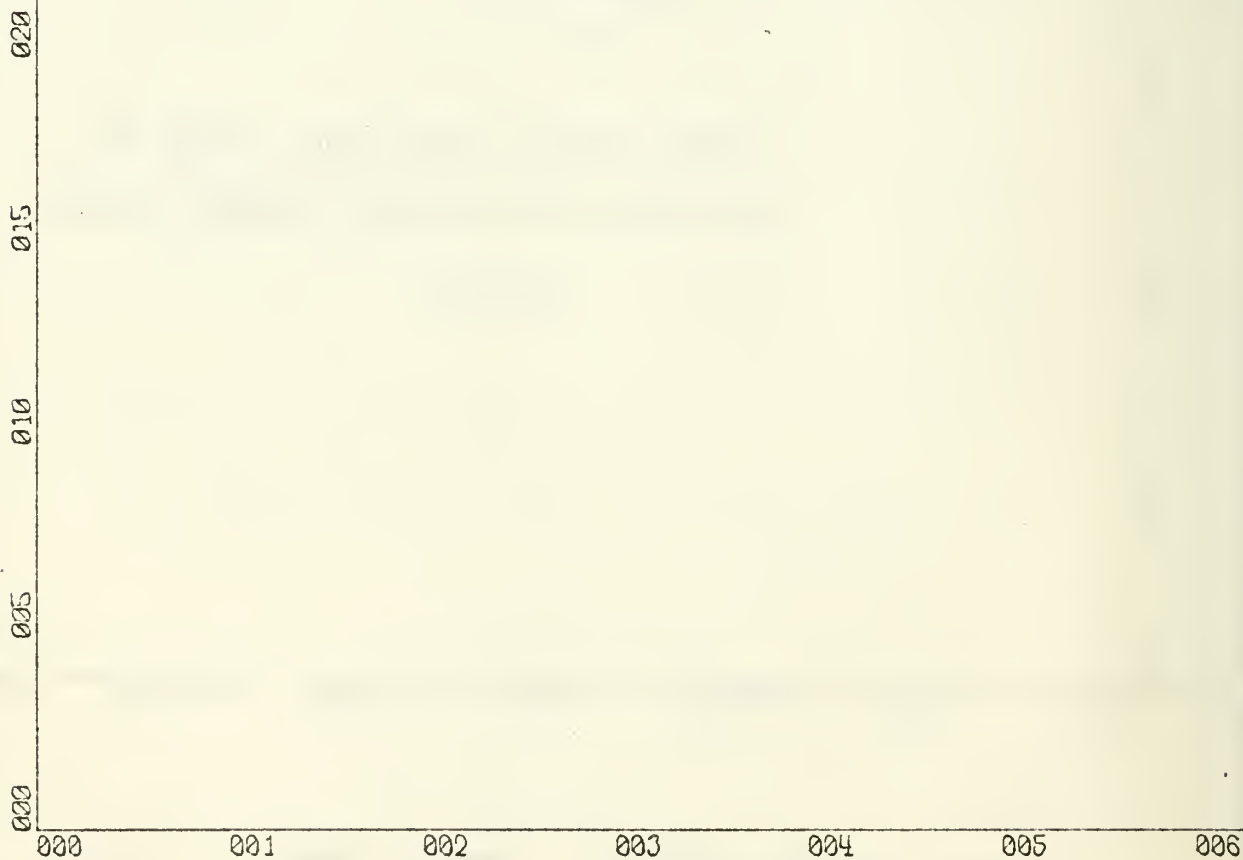
# MISSILE ACTIVE GUIDANCE SIMULATION

A-1-2-0.1-0.1

Range (program termination) - 30.9 ft.

Predicted miss distance - 5.07 ft (right)

Figure 5-5



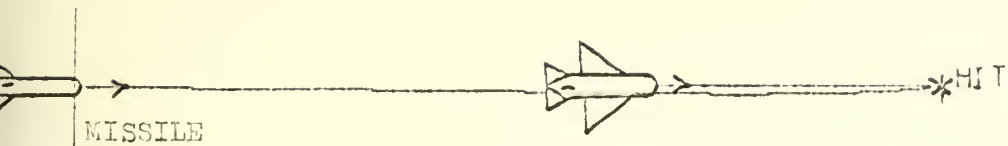
X-SCALE =  $1.00E+04$  UNITS/INCH.

Y-SCALE =  $5.00E+03$  UNITS/INCH.

(units - feet)

Y

TARGET



0.35

0.30

0.25

0.20

0.15

0.10

0.05

0.00

MISSILE ACTIVE GUIDANCE SIMULATION

A-1-2-0.01-0.01

Range (program termination) = 3.8 ft.

Predicted miss distance = 0.01 ft. (left)

Figure 5-6

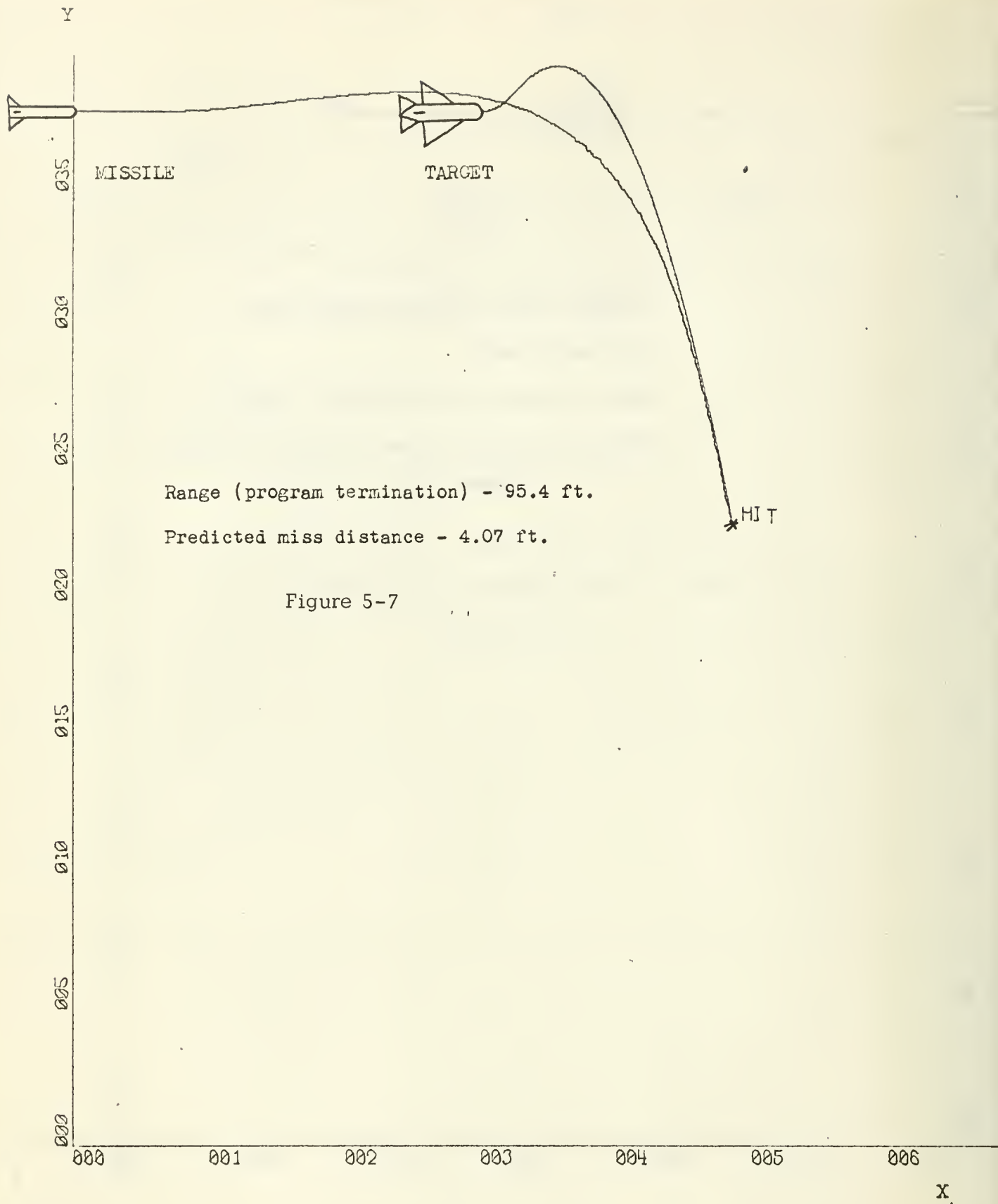
0.00 0.01 0.02 0.03 0.04 0.05 0.06

X

X-SCALE =  $1.00E+04$  UNITS/INCH.

(Units = feet)

Y-SCALE =  $5.00E+03$  UNITS/INCH.



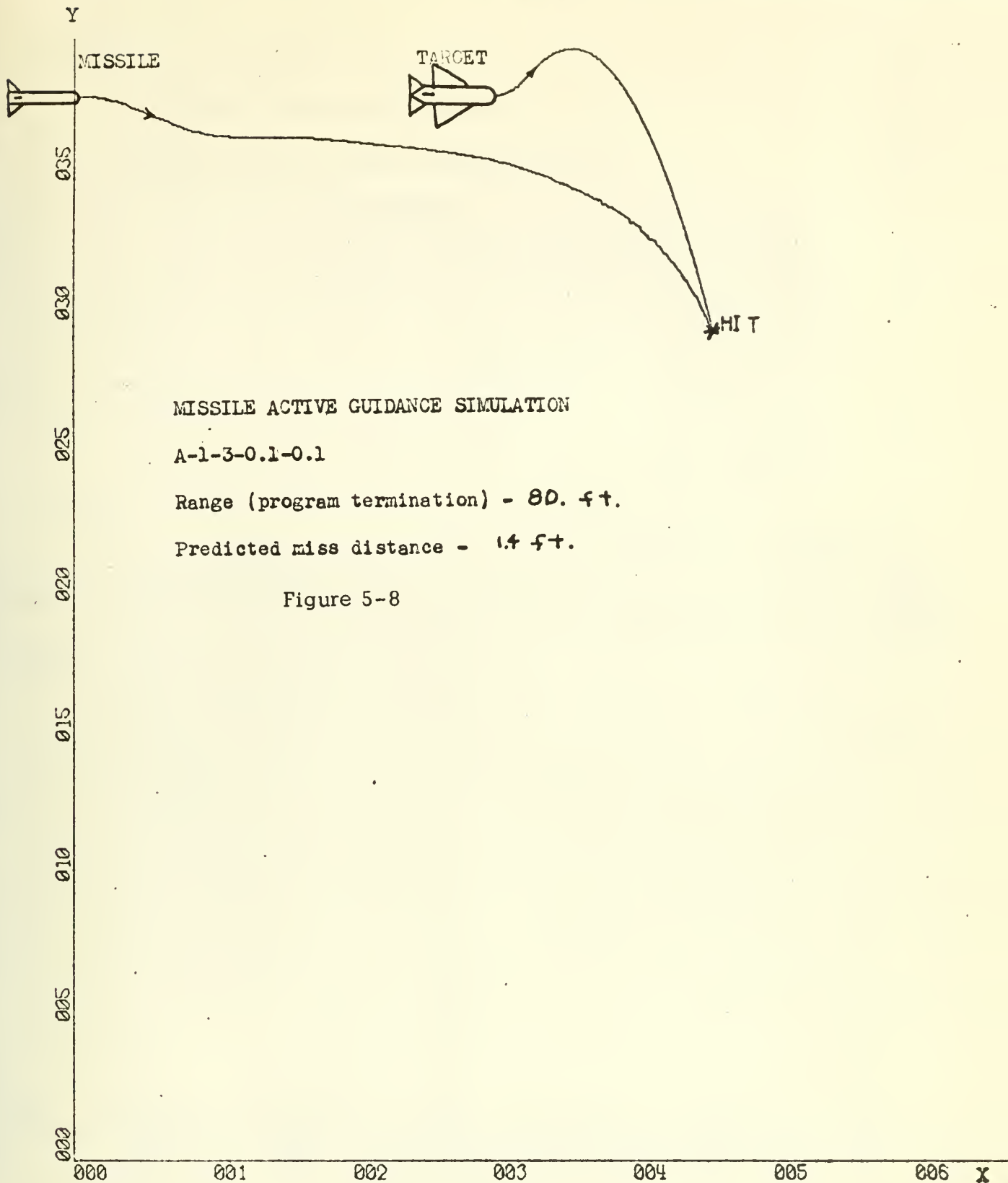
X-SCALE = 1.00E+04 UNITS/INCH.

(units - feet)

Y-SCALE = 5.00E+03 UNITS/INCH.

SIMULATION OF GUIDED MISSILE/FILTER(STEELE)

A-1-3-0.01-0.01 STEELE



X-SCALE = 1.00E+04 UNITS/INCH.  
 Y-SCALE = 5.00E+03 UNITS/INCH.

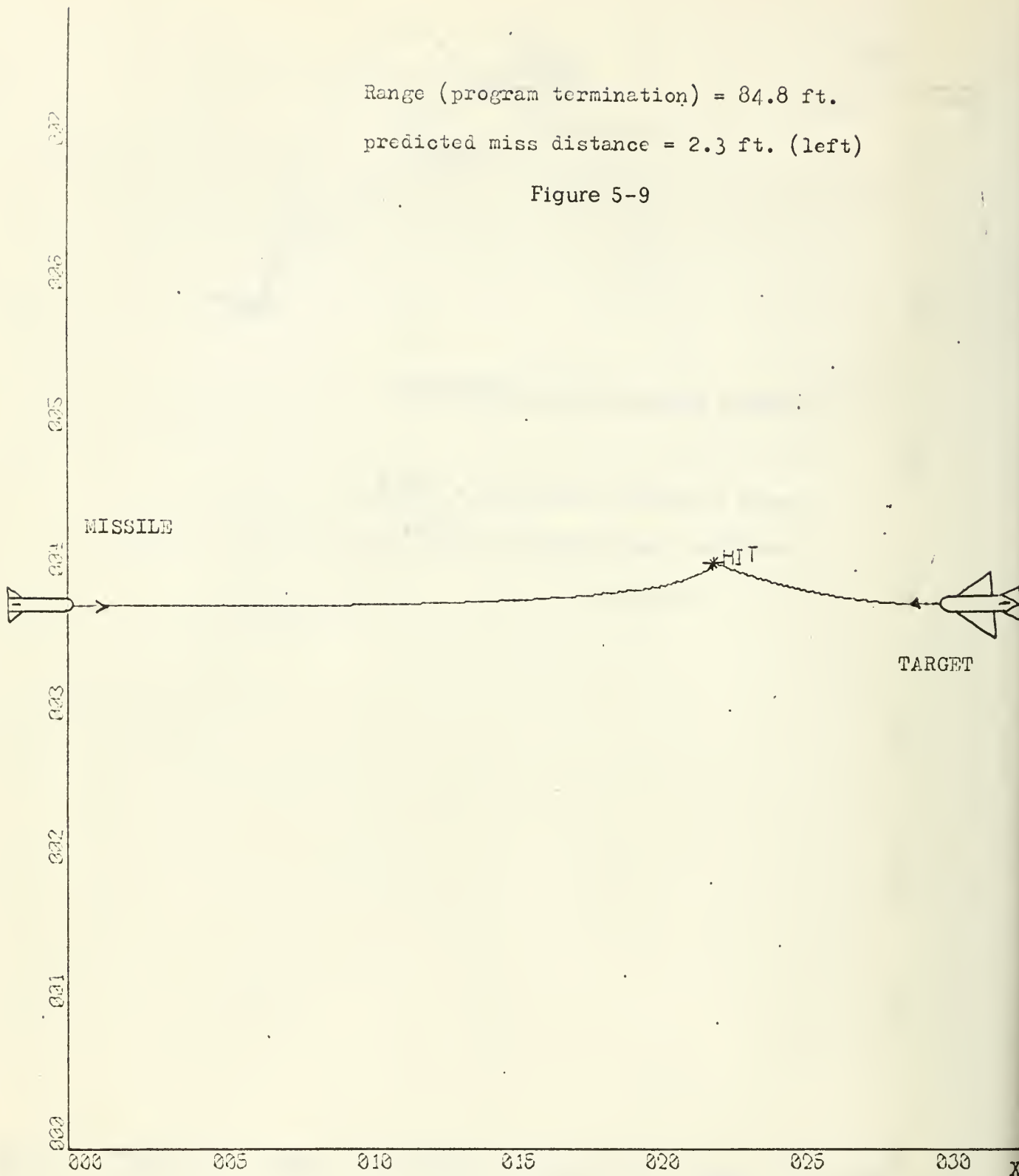
(units - feet)

Y

Range (program termination) = 84.8 ft.

predicted miss distance = 2.3 ft. (left)

Figure 5-9



K-SCALE = 5.00E+03 UNITS/INCH.

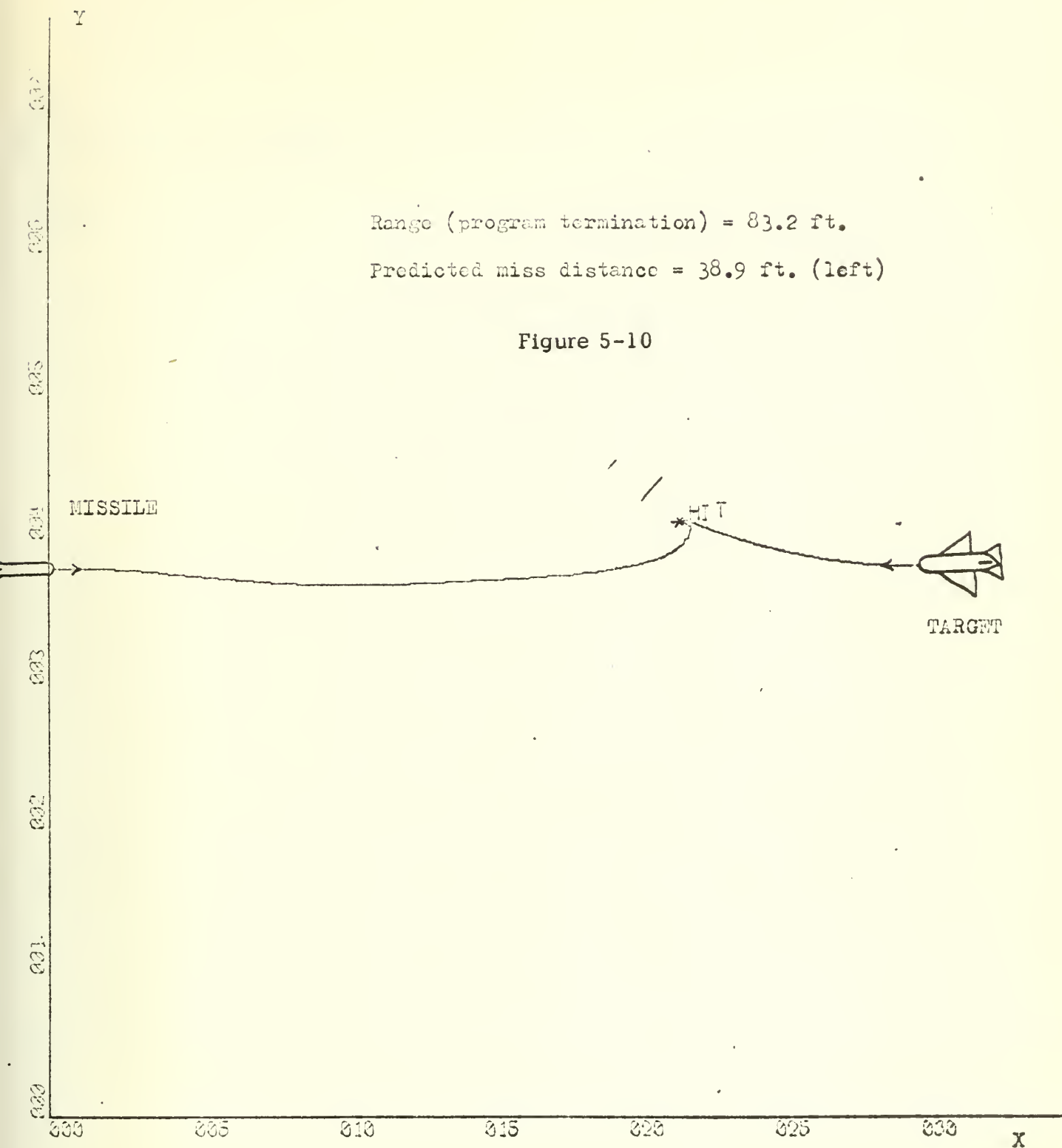
(Units = feet)

Y-SCALE = 1.00E+04 UNITS/INCH.

MISSILE ACTIVE GUIDANCE SIMULATION

B-1-1-0.01-0.01





X-SCALE =  $5.00E+03$  UNITS/INCH.

(Units = feet)

Y-SCALE =  $1.00E+04$  UNITS/INCH.

MISSILE ACTIVE GUIDANCE SIMULATION

B-1-1-0.1-0.1



X-SCALE =  $5.00\text{E}+03$  UNITS/INCH.  
Y-SCALE =  $5.00\text{E}+03$  UNITS/INCH.

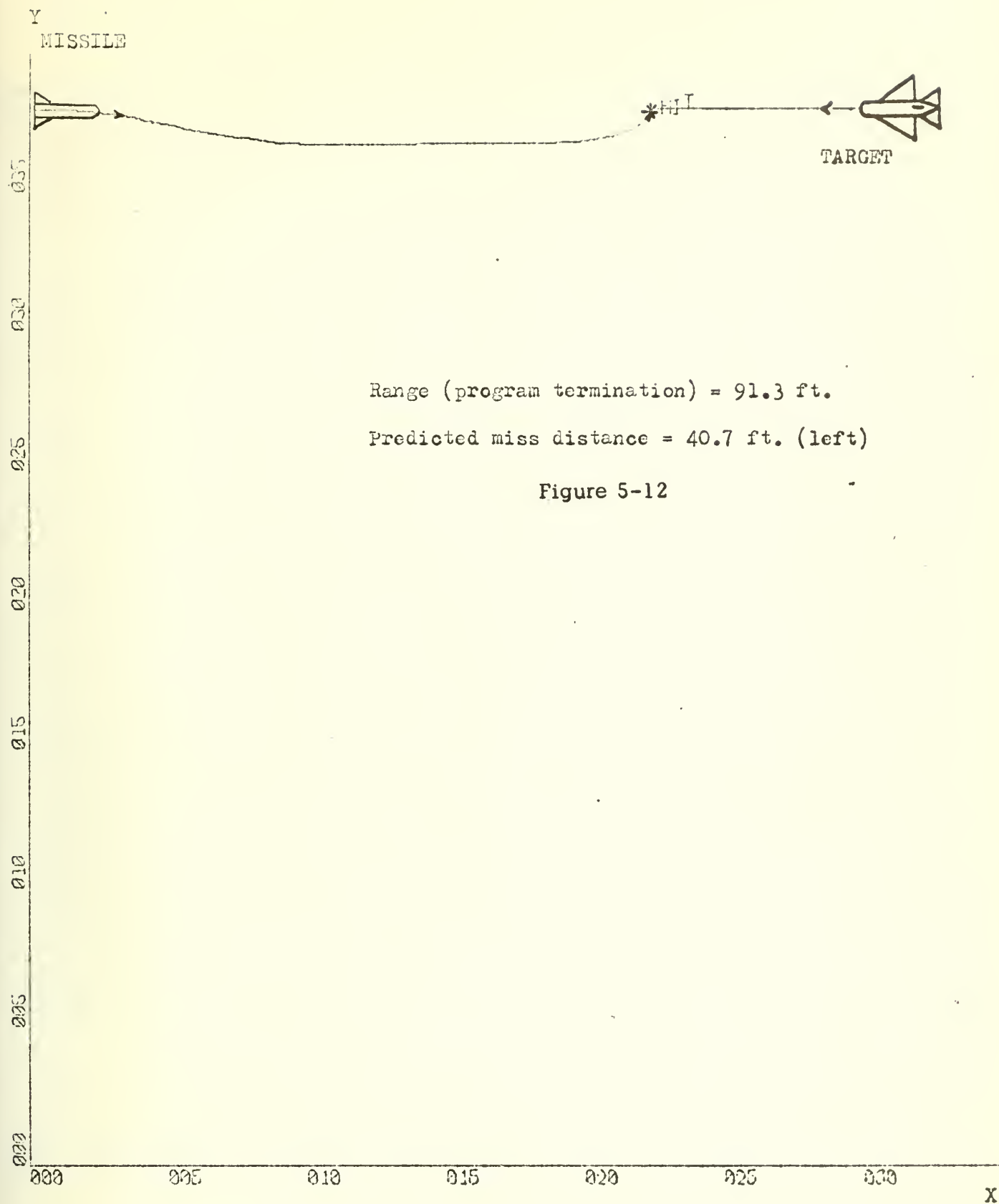
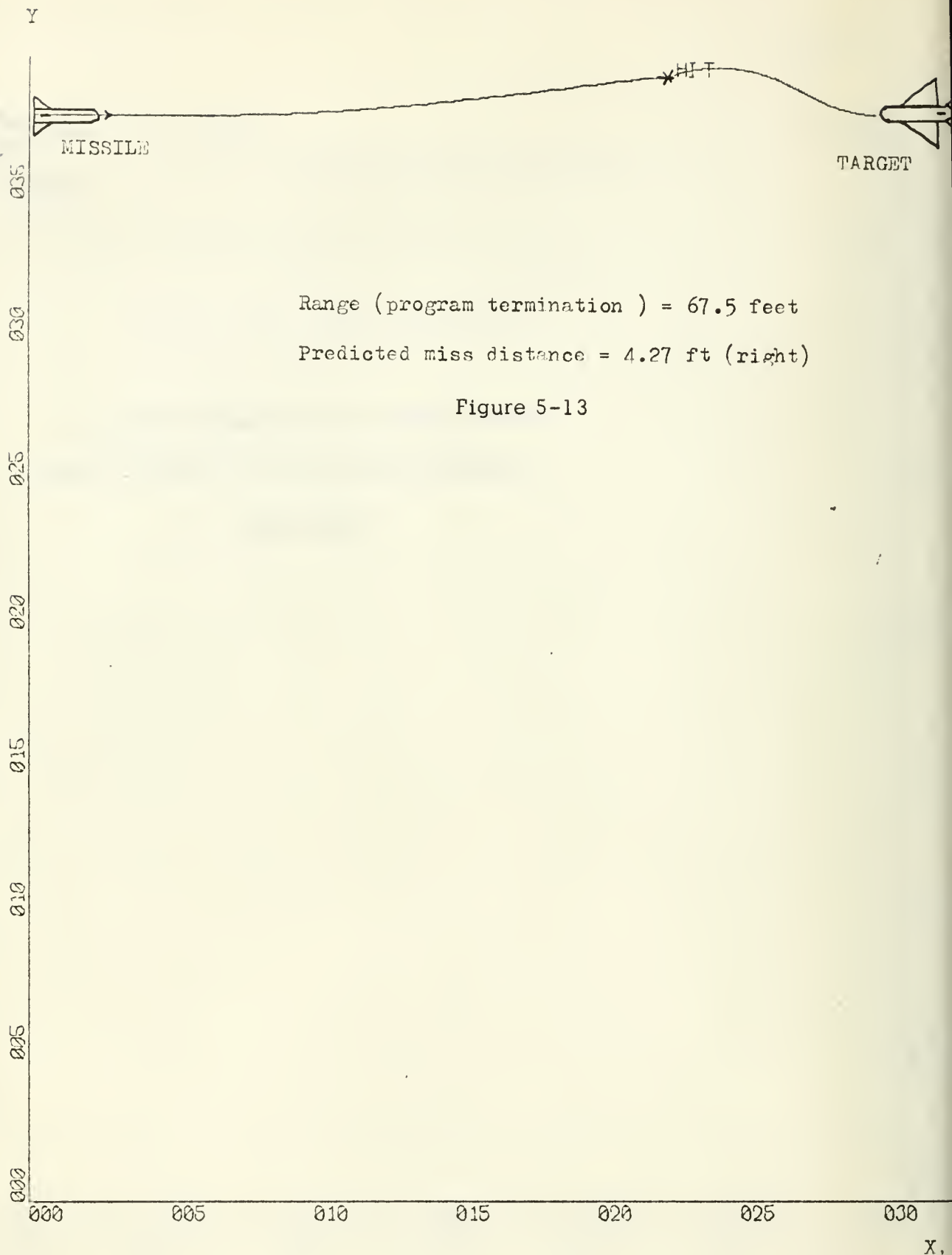


Figure 5-12

X-SCALE =  $5.00E+03$  UNITS/INCH. (units = feet)  
 Y-SCALE =  $5.00E+03$  UNITS/INCH.

MISSILE ACTIVE GUIDANCE SIMULATION

R-1-2-0.1-0.1



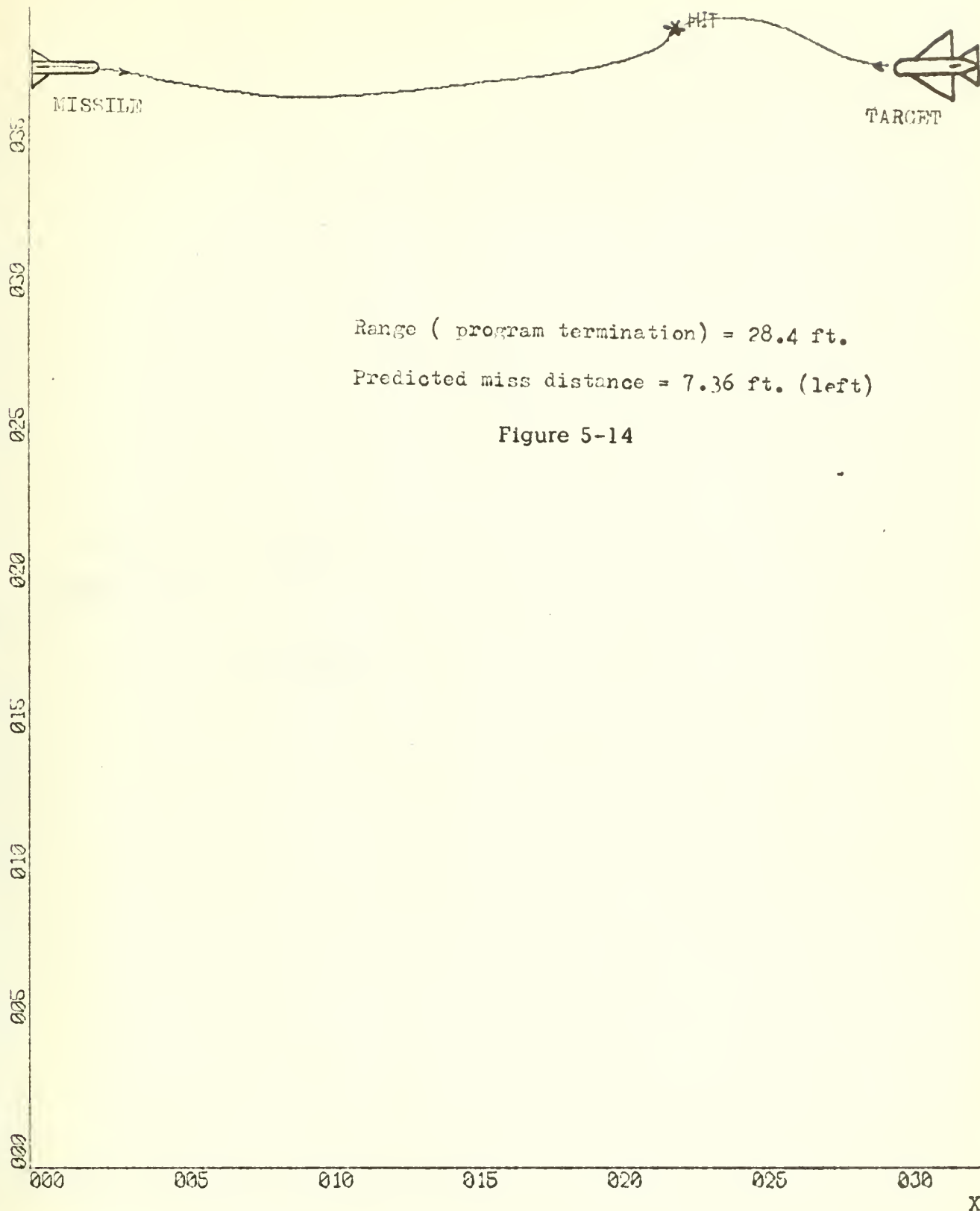
X-SCALE = 5.00E+03 UNITS/INCH.

(Units = feet)

Y-SCALE = 5.00E+03 UNITS/INCH.

MISSILE ACTIVE GUIDANCE SIMULATION

B-1-3-0.01-0.01

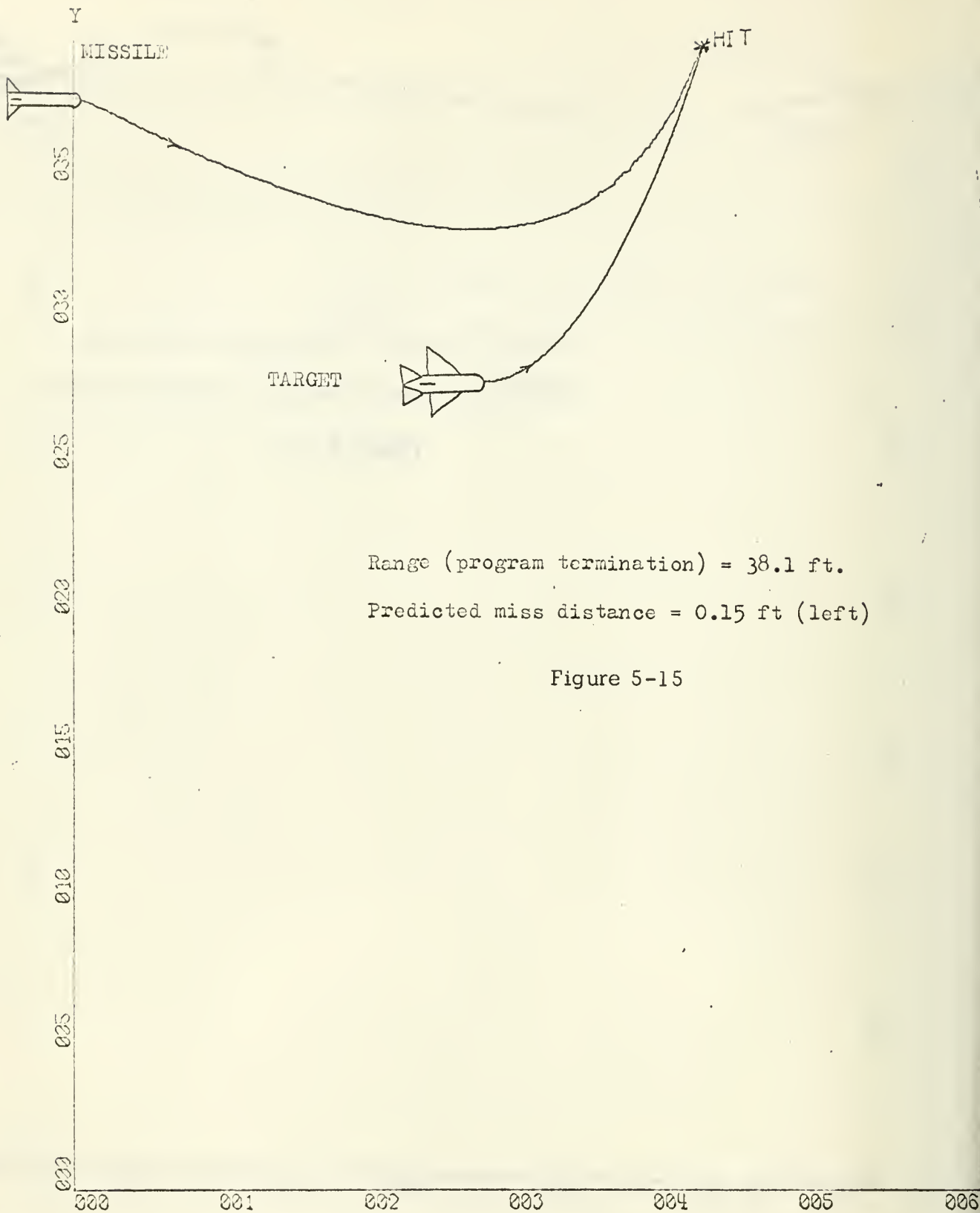


X-SCALE = 5.00E+03 UNITS/INCH. (Units = feet)

Y-SCALE = 5.00E+03 UNITS/INCH.

MISSILE ACTIVE GUIDANCE SIMULATION

B-1-3-0.1-0.1

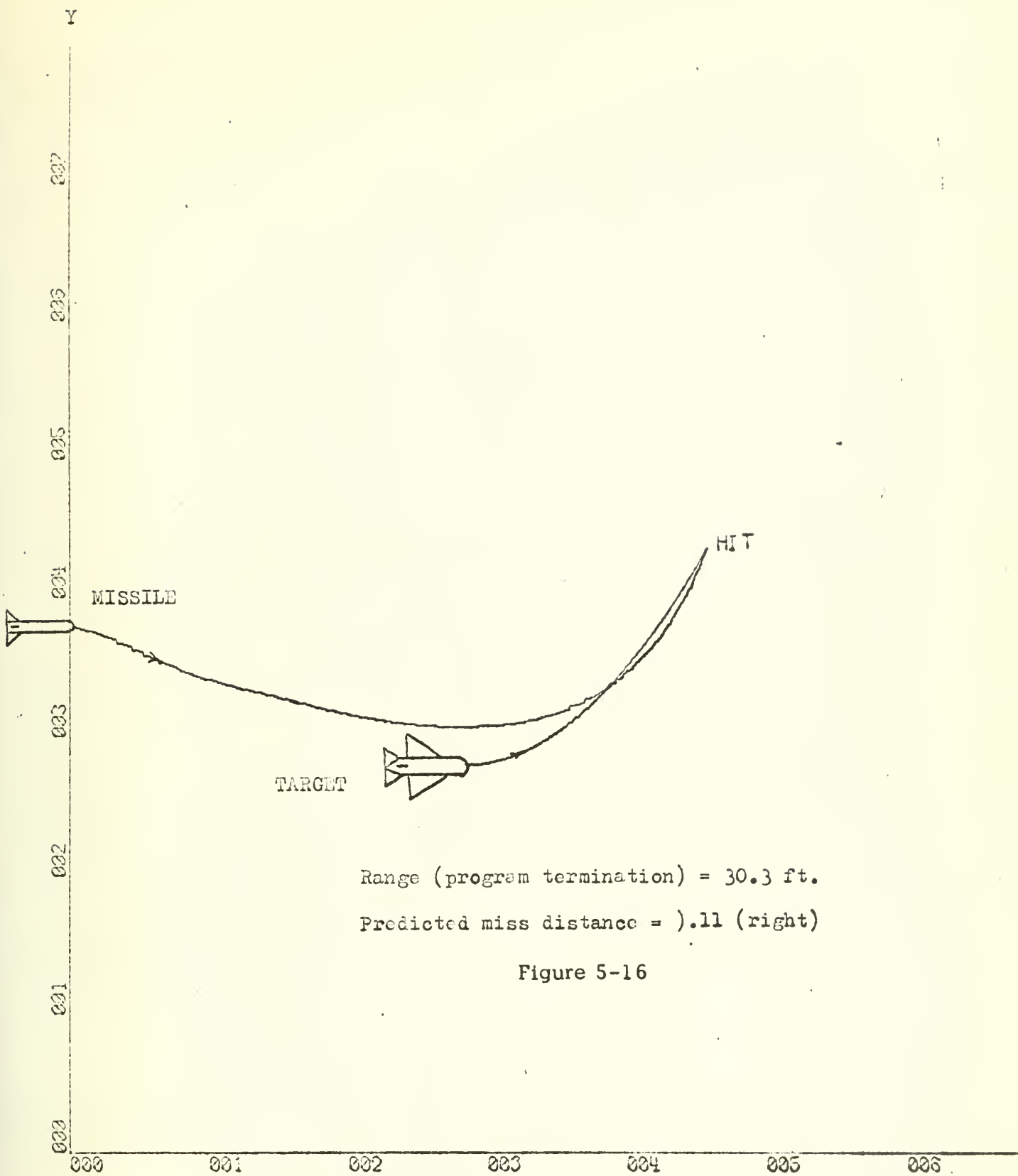


X-SCALE =  $1.00\text{E}+04$  UNITS/INCH. (Units = feet)

Y-SCALE =  $5.00\text{E}+03$  UNITS/INCH.

MISSILE ACTIVE GUIDANCE SIMULATION

C-1-1-0 01-0 01

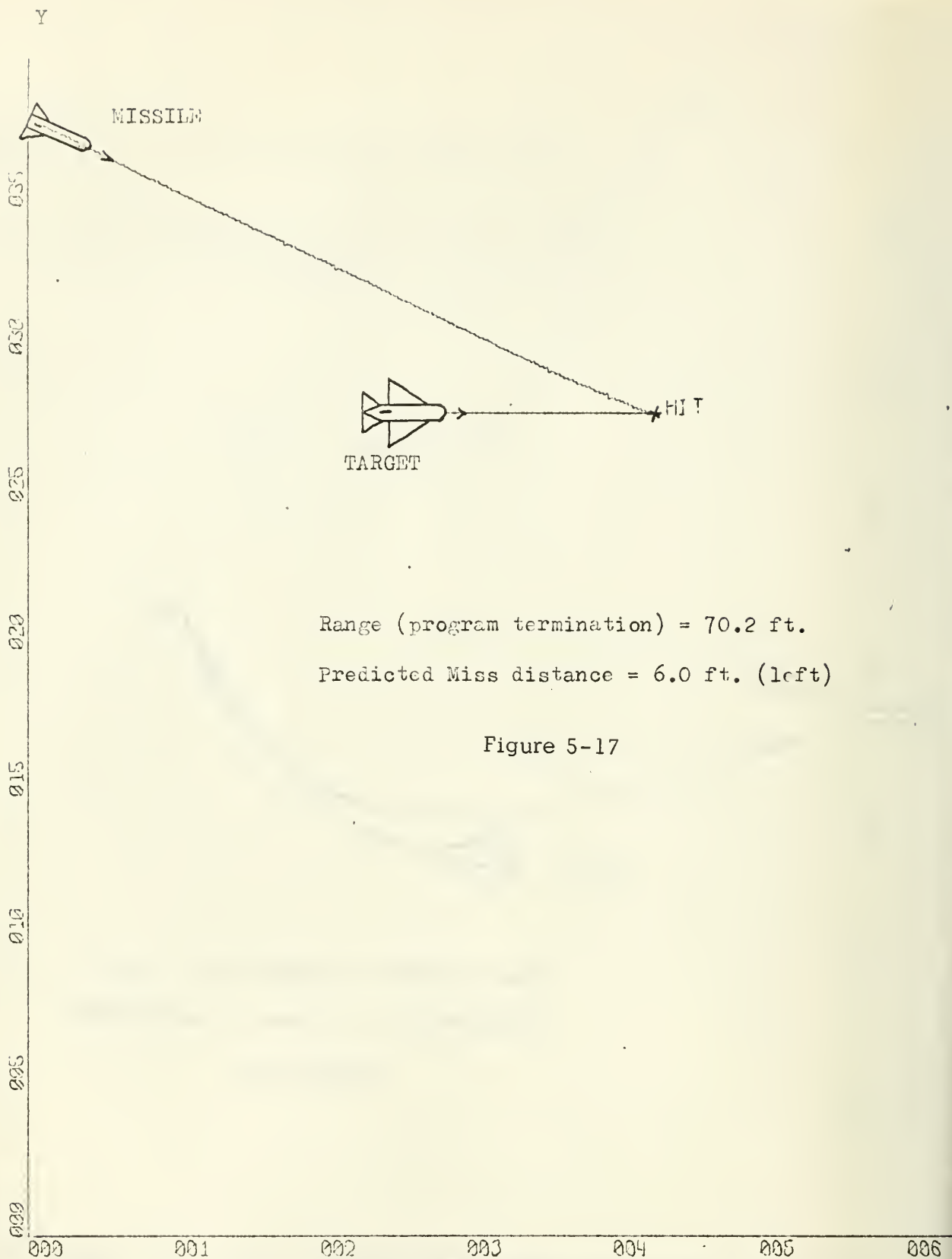


X-SCALE =  $1.00E+04$  UNITS/INCH.

Y-SCALE =  $1.00E+04$  UNITS/INCH.

MISSILE ACTIVE GUIDANCE SIMULATION

C-1-1-0 1-0 1



X-SCALE =  $1.00E+04$  UNITS/INCH.

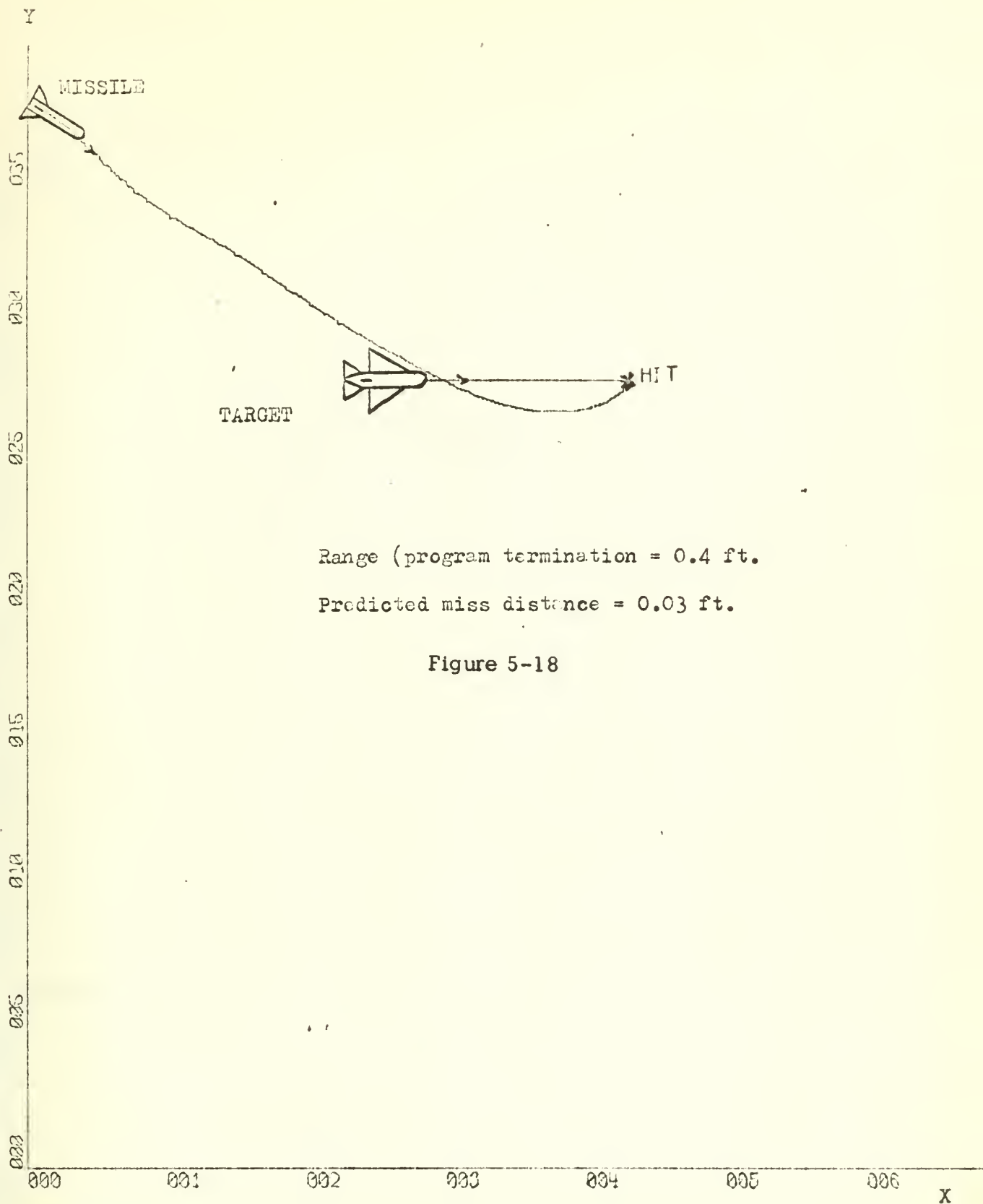
(Units = feet)

Y-SCALE =  $5.00E+03$  UNITS/INCH.

MISSILE ACTIVE GUIDANCE SIMULATION

C-1-2-0.01-0.01





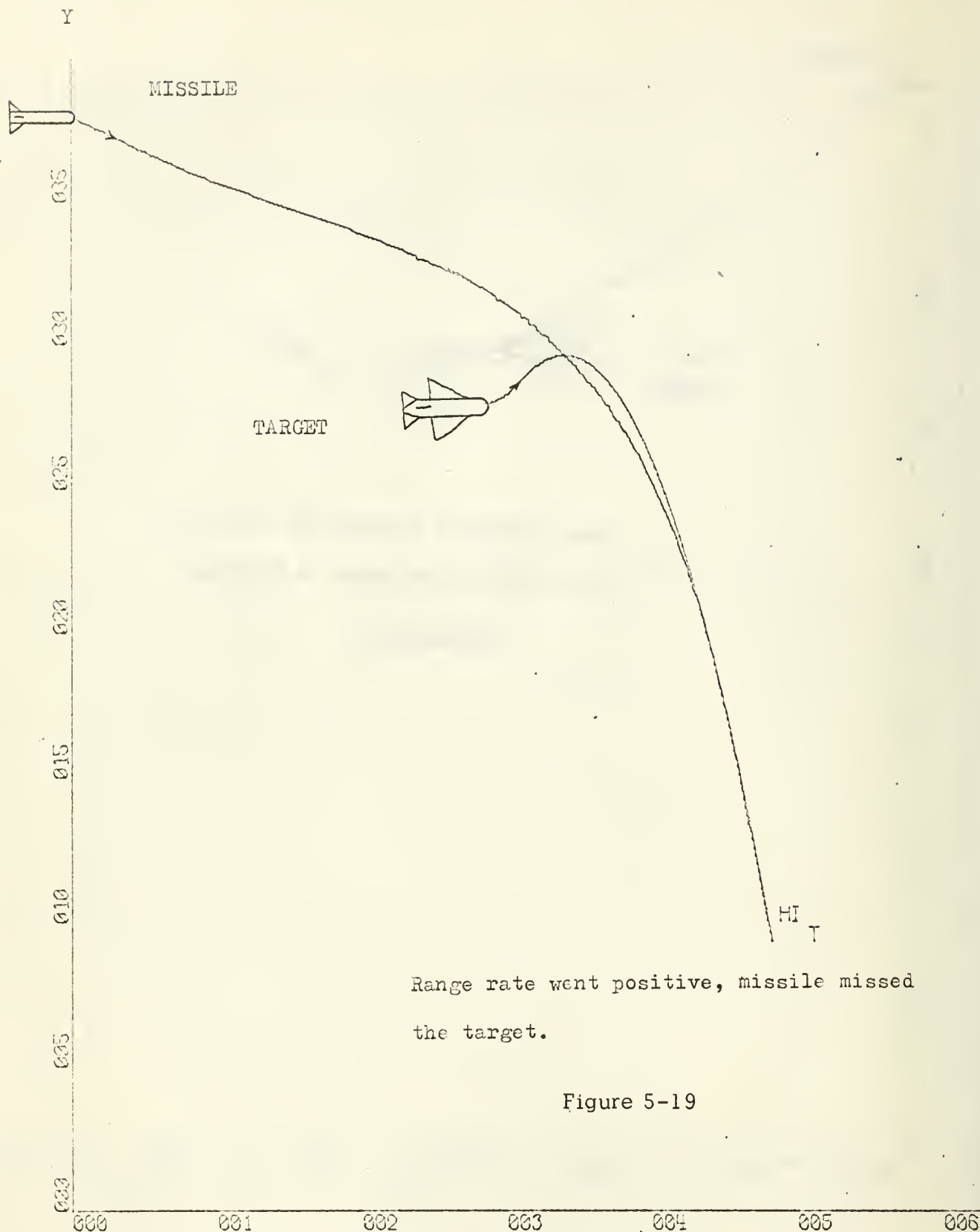
X-SCALE =  $1.00E+04$  UNITS/INCH.

(units = feet)

Y-SCALE =  $5.00E+03$  UNITS/INCH.

MISSILE ACTIVE GUIDANCE SIMULATION

C-1-2-0.1-0.1

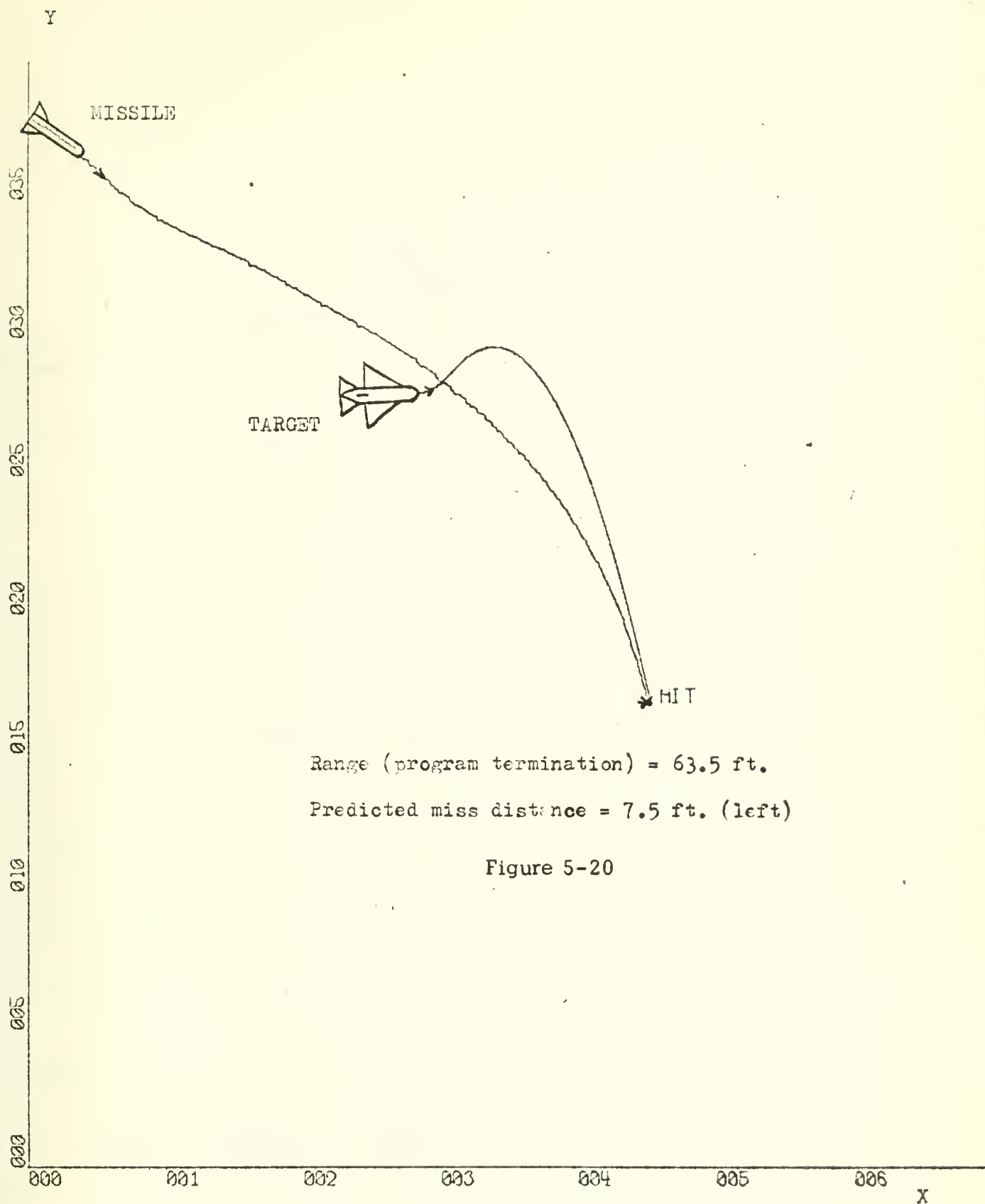


X-SCALE =  $1.00E+04$  UNITS/INCH.

Y-SCALE =  $5.00E+03$  UNITS/INCH.

(units = feet)

MISSILE ACTIVE GUIDANCE SIMULATION



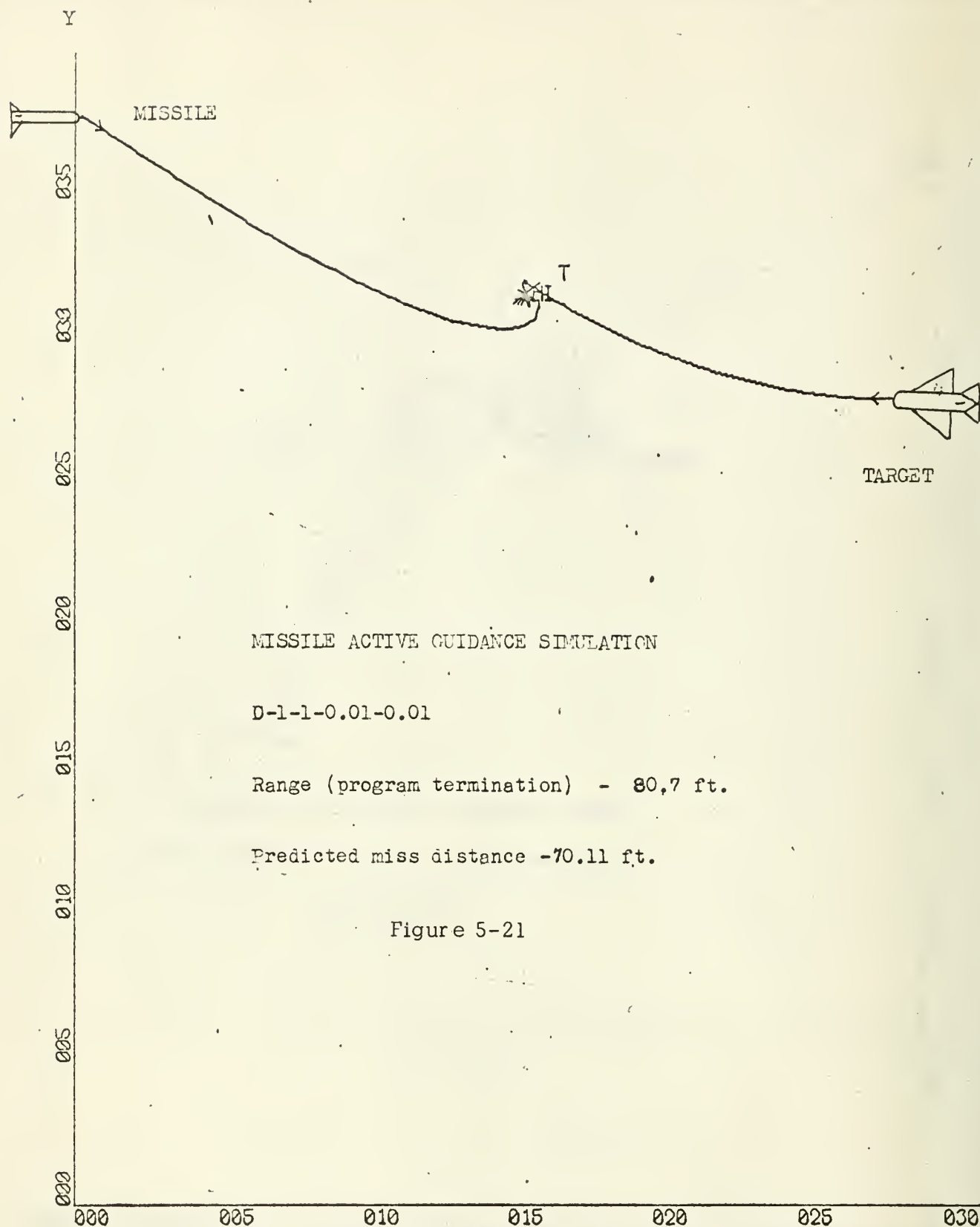
X-SCALE = 1.00E+04 UNITS/INCH.

(units = feet)

Y-SCALE = 5.00E+03 UNITS/INCH.

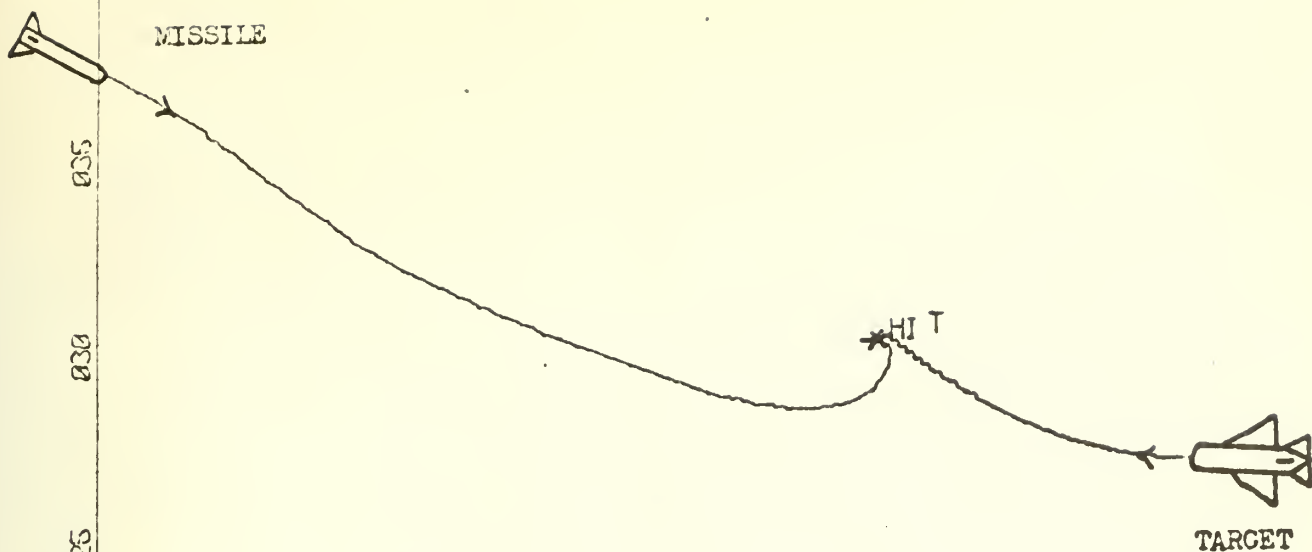
MISSILE ACTIVE GUIDANCE SIMULATION

C-1-3-0 1-0 1



X-SCALE =  $5.00\text{E}+03$  UNITS/INCH.  
 Y-SCALE =  $5.00\text{E}+03$  UNITS/INCH.

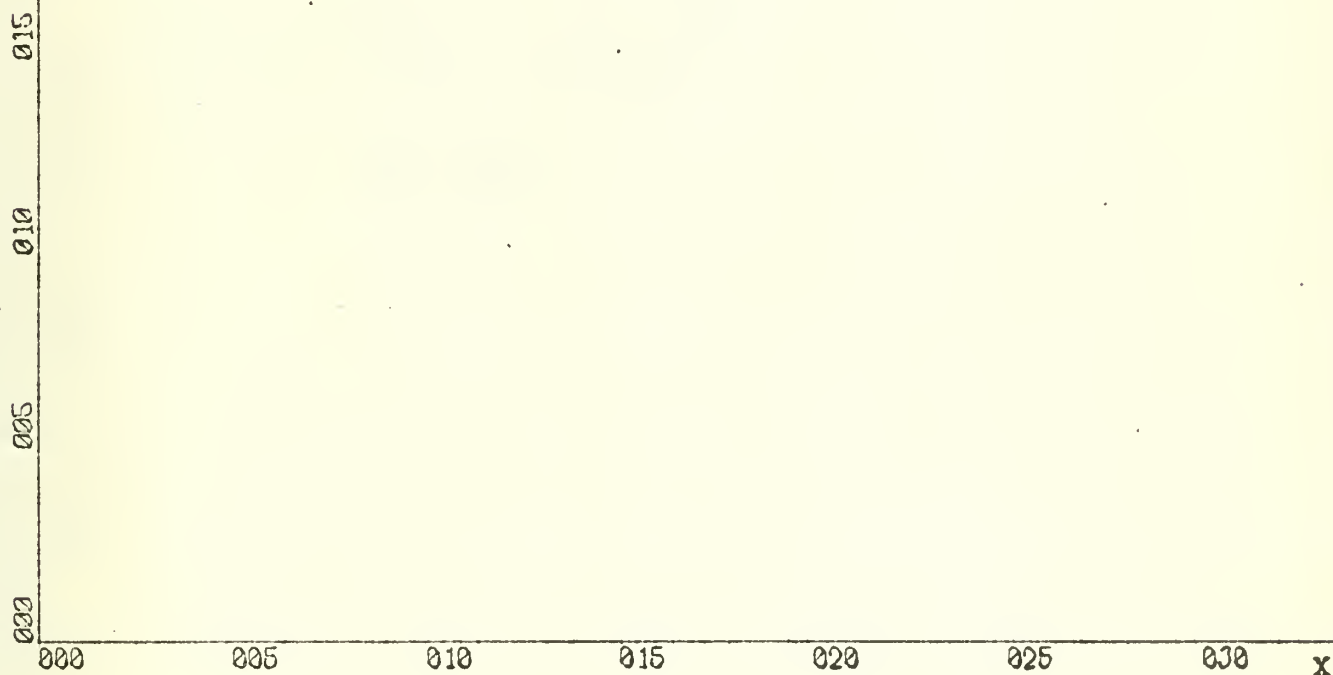
64 (units - feet)



Range (program termination) - 5.6 feet

Predicted miss distance - 0.1 ft.

Figure 5-22



X-SCALE =  $5.00E+03$  UNITS/INCH.

(units - feet)

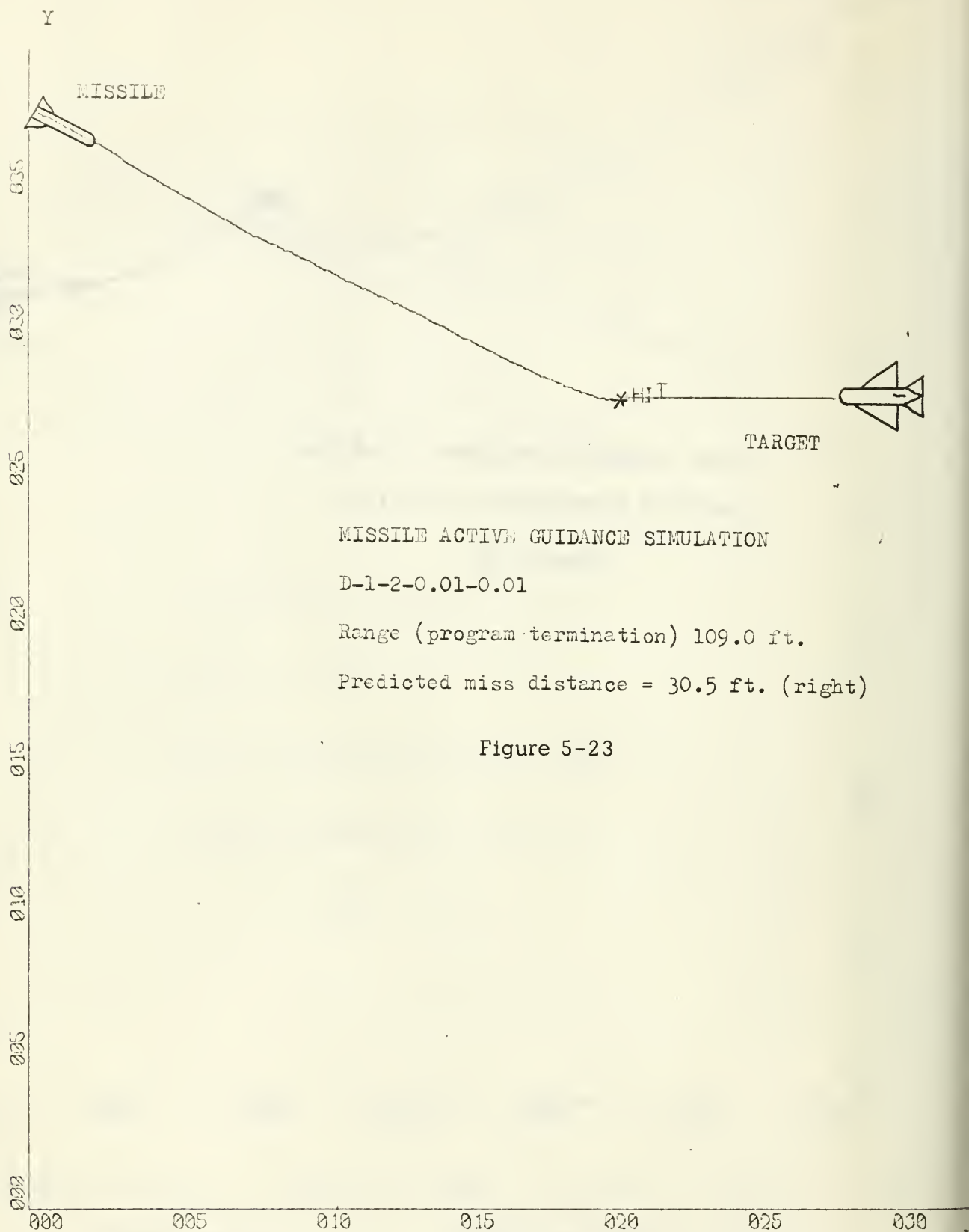
Y-SCALE =  $5.00E+03$  UNITS/INCH.

MISSILE ACTIVE GUIDANCE SIMULATION

D-1-1-0.1-0.1

65

STEELE



X-SCALE =  $5.00E+03$  UNITS/INCH. (units = feet)

Y-SCALE =  $5.00E+03$  UNITS/INCH.

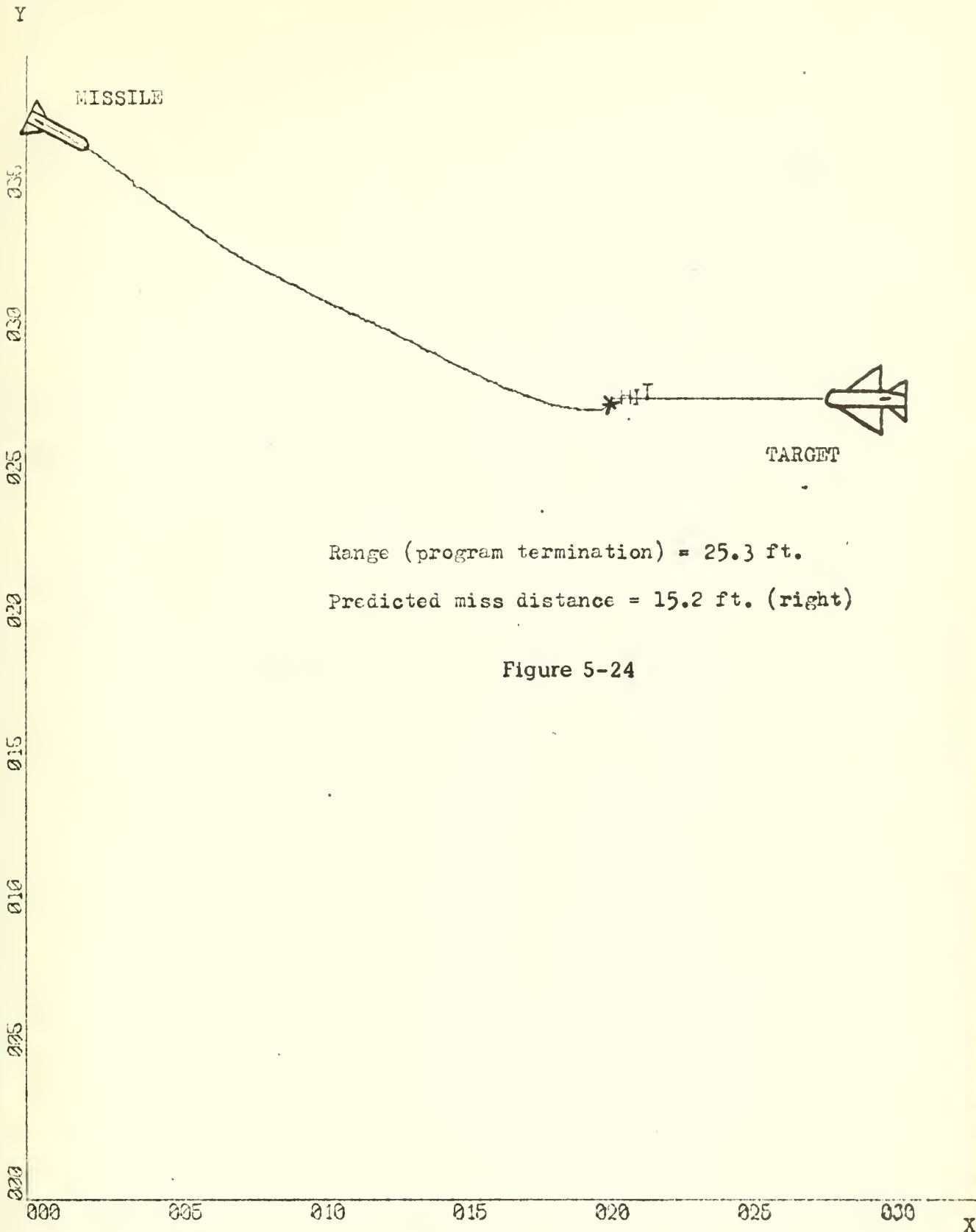


Figure 5-24

X-SCALE =  $5.00E+03$  UNITS/INCH.

(Units = feet)

Y-SCALE =  $5.00E+03$  UNITS/INCH.

MISSILE ACTIVE GUIDANCE SIMULATION

D-1-2-0.1-0.1

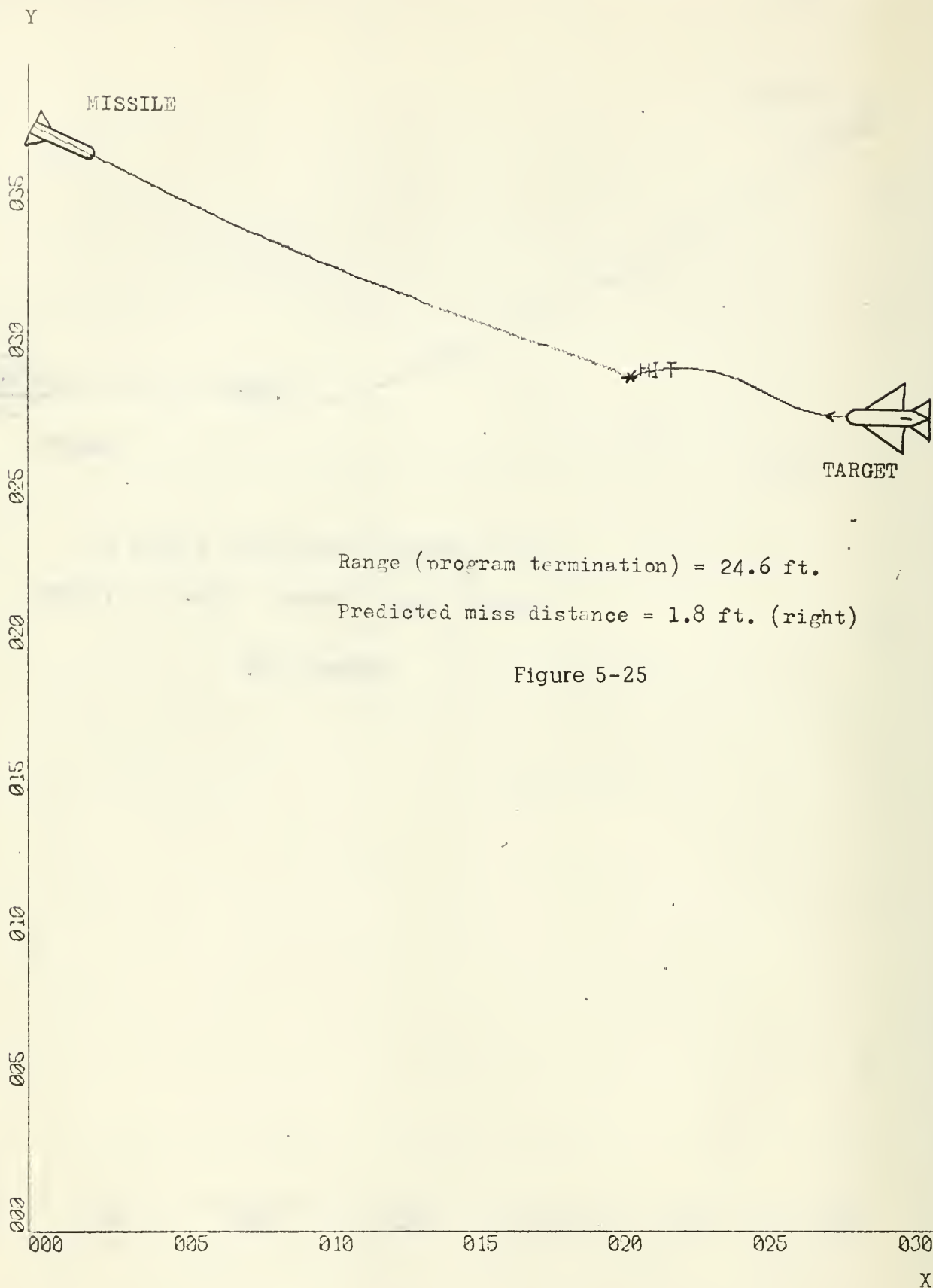


Figure 5-25

X-SCALE = 5.00E+03 UNITS/INCH.

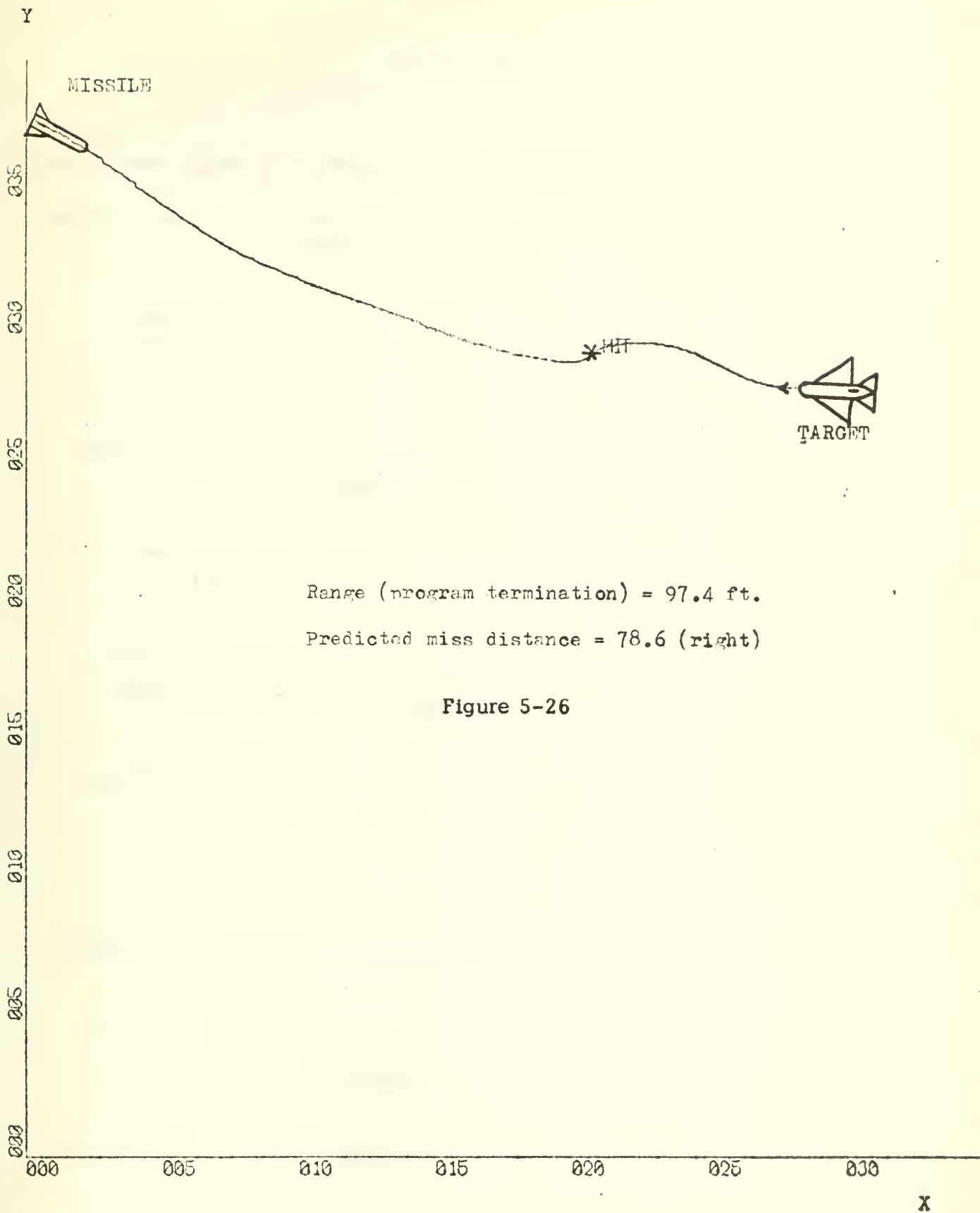
(units = feet)

Y-SCALE = 5.00E+03 UNITS/INCH.

MISSILE ACTIVE GUIDANCE SIMULATION

D-1-3-0 01-0 01





X-SCALE = 5.00E+03 UNITS/INCH.

(Units = feet)

Y-SCALE = 5.00E+03 UNITS/INCH.

MISSILE ACTIVE GUIDANCE SIMULATION

D 1 2 0 1 0 1

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## APPENDIX I

THROUGHOUT THIS THESIS COMPUTER PROGRAMS WERE USED, MADE REFERENCE TO OR EXPLAINED. THIS APPENDIX WILL LIST THESE PROGRAMS AND GIVE A BRIEF EXPLANATION OF THE DATA REQUIRED.

### PROGRAM FILTER.

THIS PROGRAM CALCULATES THE OPTIMUM STEADY-STATE GAINS G, FOR THE DIGITAL FILTER. THE DATA CARDS ARE EXPLAINED IN THE INITIAL COMMENT CARDS OF THE PROGRAM.

```

PROGRAM FILTER
C  D1 ORDER OF SYSTEM IN I2 FORMAT
C  D2 SAMPLING INTERVAL IN 8F10.0 FORMAT
C  D3 F MATRIX BY ROWS IN 8F10.0 FORMAT
C  D4 D MATRIX BY COLUMN IN 8F10.0 FORMAT
C  D5 VARIANCE OF EXCITATION NOISE SIGWSQ IN 8F10.6 FORMAT
C  D6 R COVARIANCE MATRIX OF MEASUREMENT NOISE IN 8F10.6 FORMAT
C  PHI SYSTEM TRANSITION MATRIX
C  DEL DISTRIBUTION MATRIX
C  G OPTIMUM GAIN MATRIX
C  H OBSERVABLE MATRIX
C  P BEST ESTIMATE OF ERROR COVARIANCE MATRIX
C  Q EXCITATION NOISE COVARIANCE MATRIX
  DIMENSION P(12,12),Q(12,12),H(12,12),R(12,12),G(12,12),PHIT(12,12),
  1,PHI(12,12),DEL(12),DELDELTA(12,12),DELS(12,12),DELST(12,12),
  2X(12),XHAT(12),YHAT(12),PNEW(12,12)
  READ 33, N
33 FORMAT (I2)
  READ 2,DT
  2 FORMAT(8F10.0)
  PRINT 1003
1003 FORMAT(1H1)
  CALL PHIDEL(PHI,DEL,N,DT)
  DO 1001 LL=1,4
  READ 20,SIGWSQ
  20 FORMAT(F10.6)
  DO 1001 LK=1,4
C  INITIALIZE MATRICES FOR EACH RUN
  DO 10 I=1,N
  DO 10 J=1,N
  PNEW(I,J)=0.0
  P(I,J)=0.0
  G(I,J)=0.0
  Q(I,J)=0.0
  DELDELTA(I,J)=0.0
  DELS(I,J)=0.0
10 DELST(I,J)=0.0
  READ 2001,R(1,1)

```

PROGRAM FILTER CONTINUED

```

2001 FORMAT(8F10.6)
DO 30 I=1,N
  30 DELS(I,1)=DEL(I)
  CALL TRANS(DELS,N,N,DELST)
  CALL PROD(DELS,DELST,N,N,N,DELDFLT)
  DO 40 I=1,N
  DO 40 J=1,N
  40 Q(I,J)=SIGWSQ*DELDELT(I,J)
  SIGW=SQRTF(SIGWSQ)
  PRINT 1004,SIGW
1004 FORMAT(/ 10X,5HSIGW= /,E20.8)
  P(1,1)=.02
  P(1,2)=0.0
  P(2,1)=0.0
  P(2,2)=1.0
  PRINT 2002,R(1,1),((Q(I,J),J=1,N),I=1,N),((P(I,J),J=1,N),I=1,N)
2002 FORMAT(//20X,8HR(1,1)= ,F10.6/20X,8HQ(I,J)= ,4F10.6/20X,8HP(I,J)=
1 ,4F10.6)
  H(1,1)=1.
  H(1,2)=0.0
  PRINT 700
700 FORMAT(//5X,3HG11,7X,3HG12,7X,3HG21,7X,3HG22,7X,3HP11,7X,3HP12,7X,
1 3HP21,7X,3HP22/)
  DO 1000 KK=1,40
  CALL GP(H,PHI,P,Q,R,2,1,G,PNEW)
  PRINT 800((G(I,J),J=1,N),I=1,N),((PNEW(I,J),J=1,N),I=1,N)
800 FORMAT (10F10.5)
  DO 11 I=1,N
  DO 11 J=1,N
  11 P(I,J)=PNEW(I,J)
1000 CONTINUE
  PRINT 1005
1005 FORMAT(1H1)
1001 CONTINUE
  END

```

```

SUBROUTINE GP(H,PHI,P,Q,R,KN,KP,G,PNEW)
  DIMENSION H(12,12),PHI(12,12),P(12,12),Q(12,12),R(12,12),G(12,12),
1 PNEW(12,12),HT(12,12),TV1(12,12),TV2(12,12)
  CALL TRANS(H,KP,KN,HT)
  CALL PROD(P,HT,KN,KN,KP,TV1)
  CALL PROD(H,TV1,KP,KN,KP,TV2)
  CALL ADD(TV2,R,KP,KP,TV1)
  CALL RECIP(KP,.00000000000001,TV1,TV2,KER)
  IF(KER-2) 101,110,101
110 PRINT 111
111 FORMAT(5HKER=2)
101 CALL PROD(HT,TV2,KN,KP,KP,TV1)
  CALL PROD(P,TV1,KN,KN,KP,G)
  CALL PROD(H,P,KP,KN,KN,TV1)
  CALL PROD(G,TV1,KN,KP,KN,TV2)

```

# PROGRAM FILTER CONTINUED

```

DO 102 I=1,KN
DO 102 J=1,KN
102 TV2(I,J)=-TV2(I,J)
CALL ADD(P,TV2,KN,KN,TV1)
CALL PROD(PHI,TV1,KN,KN,KN,TV2)
CALL TRANS(PHI,KN,KN,TV1)
CALL PROD(TV2,TV1,KN,KN,KN,PNEW)
CALL ADD(PNEW,Q,KN,KN,PNEW)
END

```

```

SUBROUTINE TRANS(A,N,M,C)
DIMENSION A(12,12),C(12,12)
DO 153 I = 1,N
DO 153 J=1,M
153 C(J,I) = A(I,J)
END

```

```

SUBROUTINE RECIP(N,EP,A,X,KER)
DIMENSION A(12,12),X(12,12)
DO 1 I=1,N
DO 1 J=1,N
1 X(I,J)=0.0
DO 2 K=1,N
2 X(K,K)=1.0
10 DO 34 L=1,N
KP=0
Z=0.0
DO 12 K=L,N
IF(Z-ABSF(A(K,L)))11,12,12
11 Z=ABSF(A(K,L))
KP = K
12 CONTINUE
IF(L-KP)13,20,20
13 DO 14 J=L,N
Z=A(L,J)
A(L,J)=A(KP,J)
14 A(KP,J)=Z
DO 15 J=1,N
Z=X(L,J)
X(L,J)=X(KP,J)
15 X(KP,J)=Z
20 IF(ABSF(A(L,L))-EP)50,50,30
30 IF(L-N)31,34,34
31 LP1=L+1
DO 36 K=LP1,N
IF(A(K,L))32,36,32
32 RATIO=A(K,L)/A(L,L)
DO 33 J=LP1,N
33 A(K,J)=A(K,J)-RATIO*A(L,J)
DO 35 J=1,N
35 X(K,J)=X(K,J)-RATIO*X(L,J)
36 CONTINUE

```



# PROGRAM FILTER CONTINUED

```

34 CONTINUE
40 DO 43 I=1,N
    II=N+1-I
    DO 43 J=1,N
        S=0.0
        IF(II-N)41,43,43
41 IIP1=II+1
    DO 42 K=IIP1,N
42 S=S+A(II,K)*X(K,J)
43 X(II,J)=(X(II,J)-S)/A(II,II)
    KER=1
    RETURN
50 KER=2
    END

```

```

C      SUBROUTINE PHIDEL(PHI,DEL,N,DT)
      VALID ONLY FOR A CONSTANT F MATRIX
      DIMENSION F(12,12),PHI(12,12),TERM(12,12),WORM(12,12)
1     DEL(12),DELM(12,12),TELM(12,12),DELP(12,12),D(12)
      READ1,((F(IR,IC),IC=1,N),IR=1,N)
1     FORMAT ((8F10.0))
      READ 1 (D(I),I=1,N)
1003 PRINT 399,DT,((F(IR,IC),IC=1,N),IR=1,N)
      399 FORMAT(///3HDT=,1F5.3///,7HF(I,J)=/,((8F8.2)))
      PRINT 3991 (D(I),I=1,N)
3991 FORMAT(///5HD(I)=/(8F8.2))
      NFINAL=1
      TM=0.0
      DO 400 IR=1,N
      DO 400 IC=1,N
          TERM(IR,IC)=0.0
          WORM(IR,IC)=0.0
          TERM(IR,IR)=1.0
          TELM(IR,IC)=TERM(IR,IC)*DT
          DELP(IR,IC)=TELM(IR,IC)
          DELM(IR,IC)=0.0
          DEL(IR)=0.0
400 PHI(IR,IC)=TERM(IR,IC)
      4 TM=1.0+TM
      DO 500 IR=1,N
      DO 500 IC=1,N
      DO 500 JN=1,N
          DELM(IR,IC)=DELM(IR,IC)-TELM(IR,JN)*F(JN,IC)*DT/(TM+1.0)
500 WORM(IR,IC)=TERM(IR,JN)*F(JN,IC)*DT/TM+WORM(IR,IC)
      DO 401 IR=1,N
      DO 401 IC=1,N
          TERM(IR,IC)=WORM(IR,IC)
          TELM(IR,IC)=DELM(IR,IC)
          DELP(IR,IC)=DELP(IR,IC)+TELM(IR,IC)
          PHI(IR,IC)=PHI(IR,IC)+TERM(IR,IC)
          DELM(IR,IC)=0.0
401 WORM(IR,IC)=0.0

```

# PROGRAM FILTER CONTINUED

```

ABC=0.0
DO 2I=1,N
DO 2J=1,N
AA=TERM(I,J)
AB=ABSF(AA)
IF(ABC-AB)3,3,2
3 ABC=AB
2 CONTINUE
IF(0.000000005-ABC)5,5,6
5 GO TO 4
6 PRINT 502,((PHI(IR,IC),IC=1,N),IR=1,N)
502 FORMAT(////9X,8HPHI(I,J)////(6E20.8))
DO 600 I=1,N
DO 600 K=1,N
DO 600 J=1,N
600 DEL(I)=DEL(I)+PHI(I,J)*DELP(J,K)*D(K)
PRINT 503 (DEL(I),I=1,N)
503 FORMAT(////9X,6HDEL(I)////(6E20.8)///)
END

```

```

SUBROUTINE ADD (A,B,N,M,C)
DIMENSION A(12,12),B(12,12),C(12,12)
DO 152 I=1,N
DO 152 J=1,M
152 C(I,J) = A(I,J) + B(I,J)
END

```

```

SUBROUTINE PROD (A,B,N,M,L,C)
DIMENSION A(12,12),B(12,12),C(12,12)
DO 151 I=1,N
DO 151 J=1,L
C(I,J) =0.
DO 151 K = 1,M
151 C(I,J) = C(I,J) + A(I,K)*B(K,J)
END
END

```

## PROGRAM OPTCON

### DATA CARDS

```

D1 CASE THE COMPUTER IS TO EXAMINE.
CASE 1 Q = I, R = 0 , Q* = 0
CASE 2 Q = 0, R = 1 , Q* = 0
CASE 3 Q = I, R = 1, Q* EMPLOYED
D2 N = ORDER OF SYSTEM, NSTAGE = NO. OF ITERATIONS
D3 Q-WEIGHTING MATRIX
D4 F MATRIX
D5 D VECTOR
D6 DT-SAMPLE PERIOD

```



```

PROGRAM OPTCON
  DIMENSION PHI(12,12),PSI(12,12),P(12,12),DEL(12),AT(12),
  1GM(12,12),Q(12,12),X(900),ITITLE(12),FM(16),EM(12),HM(12,12),
  1 Y1(900),Y2(900),Y3(900)

C THIS PROGRAM UTILIZES A COST FUNCTION,  $J(N)=\text{MINIMUM}(\text{SUM } X(N)T*Q*X(N)+$ 
C  $\text{SUM } R*U(N-1)**2)$ . AN UNLIMITED NUMBER OF ITERATIONS MAY BE MADE AT
C A COMPUTATION RATE OF 2000 PER MINUTE AFTER THE PROGRAM HAS BEEN
C COMPILED. THE OUTPUT OF THIS PROGRAM IS THE FEEDBACK GAIN MATRIX,
C A TRANSPOSE. THE FOLLOWING RECURSIVE EQUATIONS WERE DERIVED USING
C DYNAMIC PROGRAMMING,
C  $AT(K)=-(\text{DELT}*P(K-1)*PHI)/(\text{DELT}*P(K-1)*\text{DEL}+R)$  (1)
C  $PSI(K)=PHI+\text{DEL}*AT(K)$  (2)
C  $P(K)=PSIT(K)*P(K-1)*PSI(K)+Q+R*A(K)*AT(K)$  (3)
C  $P(0)=0, AT(0)=0, PSI(0)=0$ 
C EQUATIONS 1, 2, AND 3 CONSTITUTE THIS PROGRAM

C CALL IN DATA AND INITIALIZE
  DO 1111 I=1,3
    READ 30,KASE
30 FORMAT(I1)
    READ 1 ,N,NSTAGE
    1 FORMAT (8I10)
    READ 2,R,DT
    2 FORMAT((4F20.0))
    READ 2 ((Q(I,J),J=1,N),I=1,N)
C PRINT THE DATA READ IN.
    PRINT 100
100 FORMAT(1H1)
    PRINT 32,KASE
    32 FORMAT(9X,5HKASE= ,I3)
    PRINT 3,N,NSTAGE
    3 FORMAT(/9X,2HN=,I3,20X,7HNSTAGE=,I3)
    PRINT 4,R,DT
    4 FORMAT(/9X,2HR=,F15.11,2X,3HDT=,F15.11)
    PRINT 9,((Q(I,J),J=1,N),I=1,N)
    9 FORMAT(/9X,7HQ(I,J)=/(2F15.11))
    CALL PHIDEL(PHI,DEL,N,DT)
    DO 5 I=1,N
      DO 5 J=1,N
        GM(I,J)=0.0
        EM(I)=0.0
        FM(I)=0.0
    5 P(I,J)=Q(I,J)
C INITIALIZE P(0) FOR CASE TWO
    IF(KASE-2) 35,36,35
36 P(1,1)=1.0
    P(2,2)=1.0
    P(3,3)=1.0
35 CONTINUE
    PRINT 19
19 FORMAT(/2X,6HNSTAGE,4X,7HAT(1,1),3X,7HAT(1,2),4X,6HP(1,1),
  14X,6HP(1,2),4X,6HP(2,1),4X,6HP(2,2))
C CALCULATE AT(J)
    DO 22 KK=1,NSTAGE

```

PROGRAM OPTCON CONTINUED

```

DEN=0.0
DO6 I=1,N
DO6 J=1,N
6 EM(I)=EM(I)+DEL(J)*P(J,I)
DO8 I=1,N
DO7 J=1,N
7 FM(I)=FM(I)+EM(J)*PHI(J,I)
8 DEN=DEN+EM(I)*DEL(I)
DEN=-DEN-R
DO10 I=1,N
AT(I)=FM(I)/DEN
FM(I)=0.0
10 EM(I)=0.0
C CALCULATE PSI(K,I,J)
DO13 I=1,N
DO13 J=1,N
13 PSI(I,J)=PHI(I,J)+DEL(I)*AT(J)
C CALCULATE P(K,I,J)
DO 15 I=1,N
DO 15 J=1,N
DO 15 L=1,N
15 GM(I,J)=GM(I,J)+PSI(L,I)*P(L,J)
DO 17 I=1,N
DO 17 J=1,N
DO 16 L=1,N
16 HM(I,J)=HM(I,J)+GM(I,L)*PSI(L,J)

C CASE 1 TERMINAL CONTROL, OMIT Q(I,J) IN EQUATION FOR P(I,J)
C CASE2 MINIMUM FUEL OMIT Q(I,J) IN EQUATION FOR P(I,J)
IF(KASE-2) 31,31,33
31 P(I,J)=HM(I,J)+R*AT(I)*AT(J)
GO TO 17

C CASE THREE MINIMIZATION OF TIME AND FUEL
33 P(I,J)=HM(I,J)+Q(I,J)+R*AT(I)*AT(J)
17 HM(I,J)=0.0
DO18 I=1,N
DO18 J=1,N
18 GM(I,J)=0.0
PRINT 20, KK, AT(1), AT(2), P(1,1), P(1,2), P(2,1), P(2,2)
20 FORMAT(I5, (6F10.6))
22 CONTINUE
1111 CONTINUE
END
SUBROUTINE PHIDEL(PHI, DEL, N, DT)
C VALID ONLY FOR A CONSTANT F MATRIX
DIMENSION F(12,12), PHI(12,12), TERM(12,12), WORM(12,12)
1, DEL(12), DELM(12,12), TELM(12,12), DELP(12,12), D(12)
1 FORMAT ((8F10.0))
READ1, ((F(IR, IC), IC=1,N), IR=1,N)
READ 1 (D(I), I=1,N)
1003 PRINT 399, DT, ((F(IR, IC), IC=1,N), IR=1,N)
399 FORMAT(///3HDT=, 1F5.3/ , 7HF(I,J)=/, ((2F8.2)))

```

PROGRAM OPTCON CONTINUED

```

PRINT 3991 (D(I),I=1,N)
3991 FORMAT(/ 5HD(I)=/(2F8.2))
NFINAL=1
TM=0.0
DO 400 IR=1,N
DO 400 IC=1,N
TERM(IR,IC)=0.0
WORM(IR,IC)=0.0
TERM(IR,IR)=1.0
TELM(IR,IC)=TERM(IR,IC)*DT
DELP(IR,IC)=TELM(IR,IC)
DELM(IR,IC)=0.0
DEL(IR)=0.0
400 PHI(IR,IC)=TERM(IR,IC)
4 TM=1.0+TM
DO 500 IR=1,N
DO 500 IC=1,N
DO 500 JN=1,N
DELM(IR,IC)=DELM(IR,IC)-TELM(IR,JN)*F(JN,IC)*DT/(TM+1.0)
500 WORM(IR,IC)=TERM(IR,JN)*F(JN,IC)*DT/TM+WORM(IR,IC)
DO 401 IR=1,N
DO 401 IC=1,N
TERM(IR,IC)=WORM(IR,IC)
TELM(IR,IC)=DELM(IR,IC)
DELP(IR,IC)=DELP(IR,IC)+TELM(IR,IC)
PHI(IR,IC)=PHI(IR,IC)+TERM(IR,IC)
DELM(IR,IC)=0.0
401 WORM(IR,IC)=0.0
ABC=0.0
DO 2I=1,N
DO 2J=1,N
AA=TERM(I,J)
AB=ABSF(AA)
IF(ABC-AB)3,3,2
3 ABC=AB
2 CONTINUE
IF(0.000000005-ABC)5,5,6
5 GO TO 4
6 PRINT 11,((PHI(I,J),J=1,N),I=1,N)
11 FORMAT(/9X,9HPHI(I,J)=/(2F15.11))
DO 600 I=1,N
DO 600 K=1,N
DO 600 J=1,N
600 DEL(I)=DEL(I)+PHI(I,J)*DELP(J,K)*D(K)
PRINT 12,(DEL(I),I=1,N)
12 FORMAT(9X,7HDEL(I)=/(1F15.11))
END
END

```

# PROGRAM MISSILE

THIS PROGRAM SIMULATES THE MISSILE CONTROL, DYNAMICS, AND KINEMATICS. THE KALMAN FILTER AND OPTIMAL CONTROL IS APPLIED TO THE CONTROL OF THE PLANT.

THIS PROGRAM USES VARIABLE FILTER GAINS

THIS PROGRAM CLOSSES THE LOOP ON THE OPTIMUM FILTER-CONTROLLER PROBLEMS. IT ASSUMES THAT STABLE CONTROLLER GAIN MATRIX HAS BEEN COMPUTED ON THE BASIS OF DESIRED RESPONSE AND CALCULATES THE FILTER GAIN MATRIX EACH SAMPLE ON THE BASIS OF THE STATISTICAL PROPERTIES OF THE ANTICIPATED RANDOM DISTURBANCES.

THE PROGRAM SOLVES THE FOLLOWING EQUATIONS

$$Y(K) = H * X(K)$$

$$Z(K) = Y(K) + V(K)$$

$$X(K) = (I - GH) * PHI * X(K-1) + (I - GH) * DEL * AT * (X(K-1) - DINP(K-1)) + G * Z(K)$$

$$X(K+1) = PHI * X(K) + DEL * W(K) + DEL * AT * (X(K) - DINP(K))$$

WHERE V IS MEASUREMENT NOISE, W IS THE RANDOM DISTURBANCE, AND DINP IS THE DETERMINISTIC INPUT

## DATA CARDS.

D1 N = ORDER OF SYSTEM, DT = SAMPLE PERIOD

D2 GAMMA = FLIGHT PATH ANGLE

SIGMA = LOS ANGLE

GAMDOT = FLIGHT PATH ANGULAR RATE

DSIG = LOS ANGULAR RATE

D3 RLOS = RANGE

RZ = REQUIRED TARGET RANGE FOR HIT

XTZ = INITIAL X-COORDINATE OF TARGET

XTDOT = INITIAL VELOCITY IN X DIRECTION FOR THE TARGET

YTZ = INITIAL Y-COORDINATE OF TARGET

YTDOT = INITIAL VELOCITY IN Y DIRECTION FOR THE TARGET

D4 INITIAL CONDITIONS OF THE STATE VECTOR

D5 XMZ INITIAL X-COORDINATE OF MISSILE

YMZ INITIAL Y-COORDINATE OF MISSILE

VM MISSILE SPEED

D6 P-BEST ESTIMATE OF ERROR

D7 F MATRIX

D8 D VECTOR

D9 GRAPH TITLE LINE ONE

D10 AT FEEDBACK GAIN MATRIX FOR CONTROLLER

D11 GRAPH TITLE LINE TWO

D12 SIGW = STANDARD DEVIATION OF EXCITATION NOISE

SIGV = STANDARD DEVIATION OF MEASUREMENT NOISE

DIMENSION X(12,12), XS(12,12), SIGV(12), Y(12,12), Z(12,12), PHI(12,12),  
1, DEL(12,12), H(12,12), AT(12,12), G(12,12), TEMP1(12,12), TEMP2(12,12),  
2TEMP3(12,12), TEMP4(12,12), TELP(12,12), TELP1(12,12), TELP2(12,12),  
3V(12,12), DINP(12,12), IT(12), TME(900), YT(900), XT(900)  
4, XM(900), YM(900), P(12,12), R(12,12)

PROGRAM MISSILE CONTINUED

```

5,DELTR(12,12),DELS(12),Q(12,12)
6,SDOT(900),DIFF(900)
C   INPUT SOME CONSTANTS, AS NOTED
   READ 2,N,DT
   READ 1,GAMMA,SIGMA,GAMDOT,DSIG
   READ 1,RLOS,RZ,XTZ,XTDOT,YTZ,YTDOT
   READ 1,(X(I,1),I=1,N)
   READ 1,XMZ,YMZ,VM
3  FORMAT(6A8)
2  FORMAT(I5,1F10.0)
1  FORMAT((8F10.0))
   READ 1,((P(I,J),J=1,N),I=1,N)
   CALL PHIDEL(PHI,DELS,N,DT)
   READ 3,(IT(I),I=1,6)
   READ 1,(AT(1,I),I=1,N)
   READ 3,(IT(I),I=7,12)
   READ 1,SIGW,SIGV(1)
   PRINT 144
144 FORMAT(4X,8HXMISSILE,6X,8HXTARGET ,8X,8HYMISSILE,8X,8HYTARGET )
   DO 6000 I=1,N
6000 DEL(I,1)=DELS(I)
   CALL TRANS(DEL,N,N,DELTR)
   CALL PROD(DEL,DELTR,N,N,N,Q)
   DO 200 J=1,N
   DO 200 I=1,N
200  Q(I,J)=Q(I,J)*SIGW*SIGW
   R(1,1)=SIGV(1)*SIGV(1)
   P(1,1)=R(1,1)
C   KN IS SYSTEM ORDER. KP IS THE NUMBER OF OBSERVABLES.
   KN =N
   KP=1
   H(1,1)=1.0
C   SETTING DINP=0.0 AT THIS POINT INSURES THAT NO DETERMINISTIC
C   INPUTS EXIST PRIOR TO TIME = ZERO
   DO 131 I=1,KN
131  XS(I,1)=0.0
   NUNIF=1220703125
C   FILTER INITIAL CONDITIONS
   CALL PROD(H,X,KP,KN,KP,Y)
   DO 12 I=1,KP
   CALL RNDEV(NUNIF,DEV)
12  V(I,1)=SIGV(I)*DEV
   CALL ADD(Y,V,KP,1,Z)
   XS(1,1)=Z(1,1)
   KK=1
   T=0.0
   KK1=0
C   THIS SECTION CALCULATES G, THE GAIN MATRIX
C
6009 CALL FILTER(KN,KP,PHI,Q,R,H,P,G)
C
C   THIS SECTION CALCULATES XS, THE BEST ESTIMATE

```



# PROGRAM MISSILE CONTINUED

```

C      OF THE STATE VECTOR
      CALL PROD(H,X,KP,KN,1,Y)
      DO 10 I=1,KP
      CALL RNDEV(NUNIF,DEV)
10    V(I,1)=SIGV(I)*DEV
      CALL ADD(Y,V,KP,1,Z)
      CALL PROD(PHI,XS,KN,KN,1,TEMP1)
      CALL PROD(G,H,KN,KP,KN,TEMP2)
      DO 11 I=1,KN
      DO 11 J=1,KN
11    TEMP2(I,J)=-TEMP2(I,J)
      CALL PROD(TEMP2,TEMP1,KN,KN,1,TEMP3)
      CALL ADD(TEMP1,TEMP3,KN,1,TEMP3)
      CALL ADD(XS,DINP,KN,1,TELP)
      CALL PROD(AT,TELP,1,KN,1,TEMP1)
      CALL PROD(DELT,TEMP1,KN,1,1,TELP)
      CALL PROD(TEMP2,TELP,KN,KN,1,TELP1)
      CALL ADD(TELP,TELP1,KN,1,TELP1)
      CALL PROD(G,Z,KN,KP,1,TELP2)
      CALL ADD(TEMP3,TELP1,KN,1,XS)
      CALL ADD(XS,TELP2,KN,1,XS)

      DINP(1,1)=-DSIG
      DINP(2,1)=-DDSIG
      SDOT(KK)=DSIG
      TME(KK)=T

C
C      THIS SECTION UPDATES THE STATE VECTOR X
C
      CALL RNDEV(NUNIF,DEV)
      W=SIGW*DEV
      CALL PROD(PHI,X,KN,KN,1,TEMP1)
      DO 803 I=1,KN
803    TEMP2(I,1)=W*DEL(I,1)
      CALL ADD(XS,DINP,KN,1,TELP)
      CALL PROD(AT,TELP,1,KN,1,TELP1)
      CALL PROD(DELT,TELP1,KN,1,1,TELP2)
      CALL ADD(TEMP1,TEMP2,KN,1,X)
      CALL ADD(X,TELP2,KN,1,X)

C
C      THIS SECTION DETERMINES THE EFFECT OF THE PLANT
C      ON THE KINEMATICS
      DKSIG=DSIG
      DIFF(KK)=X(1,1)-XS(1,1)
      GAMDOT=X(1,1)
      GDOT(KK)=GAMDOT
      GAMMA =GAMMA+GAMDOT*DT
      XMDOT=VM*COSF(GAMMA)
133    YMDOT=VM*SINF(GAMMA)
134    YRDOT =YTDOT-YMDOT
      XRDOT =XTDOT-XMDOT
      RDOT=((YRDOT*SINF(SIGMA))+(XRDOT*COSF(SIGMA)))
      RDSIG=((YRDOT*COSF(SIGMA))-(XRDOT*SINF(SIGMA)))

```

PROGRAM MISSILE CONTINUED

```

RLOS =RLOS+RDOT*DT
DSIG=RDSIG/RLOS
SIGMA =SIGMA+DSIG*DT
DDSIG=(DSIG-DKSIG)/DT
XMZ=XMZ+XMDOT*DT
YMZ = YMZ+YMDOT*DT
XM(KK)=XMZ
YM(KK)=YMZ
XTZ =XTZ+XTDOT*DT
YTZ =YTZ+YTDOT*DT
YT(KK) =YTZ
XT(KK) =XTZ
RL(KK)=RLOS
PRINT 140, KK
PRINT 141, XM(KK), XT(KK), YM(KK), YT(KK)
140 FORMAT(2X, I5)
141 FORMAT(2X, 4E16.7)
KK=KK+1
T = T + DT
PRINT 190, DSIG, SIGMA
190 FORMAT(6H DSIG=, 1E16.7, 2X, 7H SIGMA=, 1E16.7)
IF(RDOT) 146, 145, 145
145 PRINT 135, RDOT
GOTO 6013
146 IF(KK-900 ) 6012, 6012, 6013
6012 IF(RLOS-100.) 6013, 6013, 6011
6011 GOTO 6009
6013 PRINT 136, RLOS
135 FORMAT(6H RDOT=, 1E16.7)
136 FORMAT(6H RLOS=, 1E16.7)
A=ATANF(RDSIG/RDOT)
TMISS=((RLOS*RDSIG/RDOT)*COSF(A)
PRINT 137, TMISS
137 FORMAT(7H TMISS=, 1E16.7)
KK=KK-1
MC =1
LA=4H RI
CALL DRAW(KK, XM, YM, MC, 0, LA, IT, 0, 0, 0, 0, 0, 0, 7, 8, 0, LAST)
MC=3
LA=4H T
CALL DRAW(KK, XT, YT, MC, 0, LA, IT, 0, 0, 0, 0, 0, 0, 7, 8, 0, LAST)
END
SUBROUTINE PROD (A,B,N,M,L,C)
DIMENSION A(12,12), B(12,12), C(12,12)
DO 151 I=1,N
DO 151 J=1,L
C(I,J)=0.
DO 151 K=1,M
151 C(I,J)=C(I,J)+A(I,K)*B(K,J)
END
SUBROUTINE ADD (A,B,N,M,C)
DIMENSION A(12,12), B(12,12), C(12,12)
DO 152 J=1,M

```

PROGRAM MISSILE CONTINUED

```
DO 152 I=1,N
152 C(I,J)=A(I,J)+B(I,J)
END
```

```

SUBROUTINE FILTER(N,KP,PHI,Q,R,H,P,G)
C   PHI SYSTEM TRANSITION MATRIX
C   DEL DISTRIBUTION MATRIX
C   G OPTIMUM GAIN MATRIX
C   H OBSERVABLE MATRIX
C   P BEST ESTIMATE OF ERROR COVARIANCE MATRIX
C   Q EXCITATION NOISE COVARIANCE MATRIX
DIMENSION P(12,12),Q(12,12),H(12,12),R(12,12),G(12,12),PHIT(12,12),
1,PHI(12,12),DEL(12),DELDELTA(12,12),DELS(12,12),DELST(12,12),
2PNEW(12,12)
CALL GP(H,PHI,P,Q,R,N,KP,G,PNEW)
DO 11 I=1,N
DO 11 J=1,N
11 P(I,J)=PNEW(I,J)
END
```

```

SUBROUTINE GP(H,PHI,P,Q,R,KN,KP,G,PNEW)
DIMENSION H(12,12),PHI(12,12),P(12,12),Q(12,12),R(12,12),G(12,12),
1PNEW(12,12),HT(12,12),TV1(12,12),TV2(12,12)
CALL TRANS(H,KP,KN,HT)
CALL PROD(P,HT,KN,KN,KP,TV1)
CALL PROD(H,TV1,KP,KN,KP,TV2)
CALL ADD(TV2,R,KP,KP,TV1)
CALL RECIP(KP,.00000000000001,TV1,TV2,KER)
IF(KER-2) 101,110,101
110 PRINT 111
111 FORMAT(5HKER=2)
101 CALL PROD(HT,TV2,KN,KP,KP,TV1)
CALL PROD(P,TV1,KN,KN,KP,G)
CALL PROD(H,P,KP,KN,KN,TV1)
CALL PROD(G,TV1,KN,KP,KN,TV2)
DO 102 I=1,KN
DO 102 J=1,KN
102 TV2(I,J)=-TV2(I,J)
CALL ADD(P,TV2,KN,KN,TV1)
CALL PROD(PHI,TV1,KN,KN,KN,TV2)
CALL TRANS(PHI,KN,KN,TV1)
CALL PROD(TV2,TV1,KN,KN,KN,PNEW)
CALL ADD(PNEW,Q,KN,KN,PNEW)
END
```

```

SUBROUTINE TRANS(A,N,M,C)
DIMENSION A(12,12),C(12,12)
DO 153 I = 1,N
DO 153 J=1,M
153 C(I,J) = A(I,J)
END
```



PROGRAM MISSILE CONTINUED

```

SUBROUTINE TRANS(A,N,M,C)
DIMENSION A(12,12),C(12,12)
DO 153 I = 1,N
DO 153 J=1,M
153 C(J,I) = A(I,J)
END

SUBROUTINE RECIP(N,EP,A,X,KER)
DIMENSION A(12,12),X(12,12)
DO 1 I=1,N
DO 1 J=1,N
1 X(I,J)=0.0
DO 2 K=1,N
2 X(K,K)=1.0
10 DO 34 L=1,N
KP=0
Z=0.0
DO 12 K=L,N
IF(Z-ABSF(A(K,L)))11,12,12
11 Z=ABSF(A(K,L))
KP = K
12 CONTINUE
IF(L-KP)13,20,20
13 DO 14 J=L,N
Z=A(L,J)
A(L,J)=A(KP,J)
14 A(KP,J)=Z
DO 15 J=1,N
Z=X(L,J)
X(L,J)=X(KP,J)
15 X(KP,J)=Z
20 IF(ABSF(A(L,L))-EP)50,50,30
30 IF(L-N)31,34,34
31 LP1=L+1
DO 36 K=LP1,N
IF(A(K,L))32,36,32
32 RATIO=A(K,L)/A(L,L)
DO 33 J=LP1,N
33 A(K,J)=A(K,J)-RATIO*A(L,J)
DO 35 J=1,N
35 X(K,J)=X(K,J)-RATIO*X(L,J)
36 CONTINUE
34 CONTINUE
40 DO 43 I=1,N
II=N+1-I
DO 43 J=1,N
S=0.0
IF(II-N)41,43,43
41 IIP1=II+1
DO 42 K=IIP1,N
42 S=S+A(II,K)*X(K,J)
43 X(II,J)=(X(II,J)-S)/A(II,II)
KER=1

```

PROGRAM MISSILE CONTINUED

```

RETURN
50 KER=2
END
SUBROUTINE PHIDEL (PHI,DEL,N,DT)
DIMENSION F(12,12),PHI(12,12),TERM(12,12),WORM(12,12)
1, DEL(12),DELM(12,12),TELM(12,12),DELP(12,12),D(12)
C VALID ONLY FOR A CONSTANT F MATRIX
C DT= SAMPLING INTERVAL
NFINAL=1
READ 1((F(IR,IC),IC=1,N),IR=1,N)
READ 1 (D(I),I=1,N)
1 FORMAT ((8F10.0))
TM=0.0
1003 PRINT 399,DT,((F(IR,IC),IC=1,N),IR=1,N)
399 FORMAT(///4H DT=, 1F5.3///,8H F(I,J)=/,4(4E16.7/))
PRINT 3991 (D(I),I=1,N)
3991 FORMAT(///6H D(I)=/,4(1E16.7/))
DO 400 IR=1,N
DO 400 IC=1,N
TERM(IR,IC)=0.0
WORM(IR,IC)=0.0
TERM(IR,IR)=1.0
TELM(IR,IC)=TERM(IR,IC)*DT
DELP(IR,IC)=TELM(IR,IC)
DELM(IR,IC)=0.0
DEL(IR)=0.0
400 PHI(IR,IC)=TERM(IR,IC)
4 TM=1.0+TM
DO 500 IR=1,N
DO 500 IC=1,N
DO 500 JN=1,N
DELM(IR,IC)=DELM(IR,IC)-TELM(IR,JN)*F(JN,IC)*DT/(TM+1.0)
500 WORM(IR,IC)=TERM(IR,JN)*F(JN,IC)*DT/TM+WORM(IR,IC)
DO 401 IR=1,N
DO 401 IC=1,N
TERM(IR,IC)=WORM(IR,IC)
TELM(IR,IC)=DELM(IR,IC)
DELP(IR,IC)=DELP(IR,IC)+TELM(IR,IC)
PHI(IR,IC)=PHI(IR,IC)+TERM(IR,IC)
DFLM(IR,IC)=0.0
401 WORM(IR,IC)=0.0
ABC=0.0
DO 2I=1,N
DO 2J=1,N
AA=TERM(I,J)
AB=ABSF(AA)
IF(ABC-AB)3,3,2
3 ABC=AB
2 CONTINUE
IF(0.000000005-ABC)5,5,6
6 PRINT 502,((PHI(IR,IC),IC=1,N),IR=1,N)
502 FORMAT(//9X,8HPHI(I,J)///((4E16.7)))

```

PROGRAM MISSILE CONTINUED

```

DO 600 I=1,N
DO 600 K=1,N
DO 600 J=1,N
600 DFL(I)=DEL(I)+PHI(I,J)*DELP(J,K)*D(K)
PRINT 503 (DEL(I),I=1,N)
503 FORMAT(///9X,6HDEL(I)///(8F15.9)///)
RETURN
END
END

```

PROGRAM MISSILE CONTINUED

```

C      EVASION

      YTDOT =YTDOT+10.
C      EVASION LEFT-RIGHT-LEFT
      IF(KK-30)320,321,321
320 YTDOT=YTDOT+20.
      GOTO 323
321 YTDOT=YTDOT-20.
323 CONTINUE
      IF(YTZ-5000.)324,324,325
324 YTDOT=YTDOT+30.
      IF (YTZ-2000.)326,326,325
326 YTDOT=0.0
325 CONTINUE
C      END OF EVASION

```

## APPENDIX II

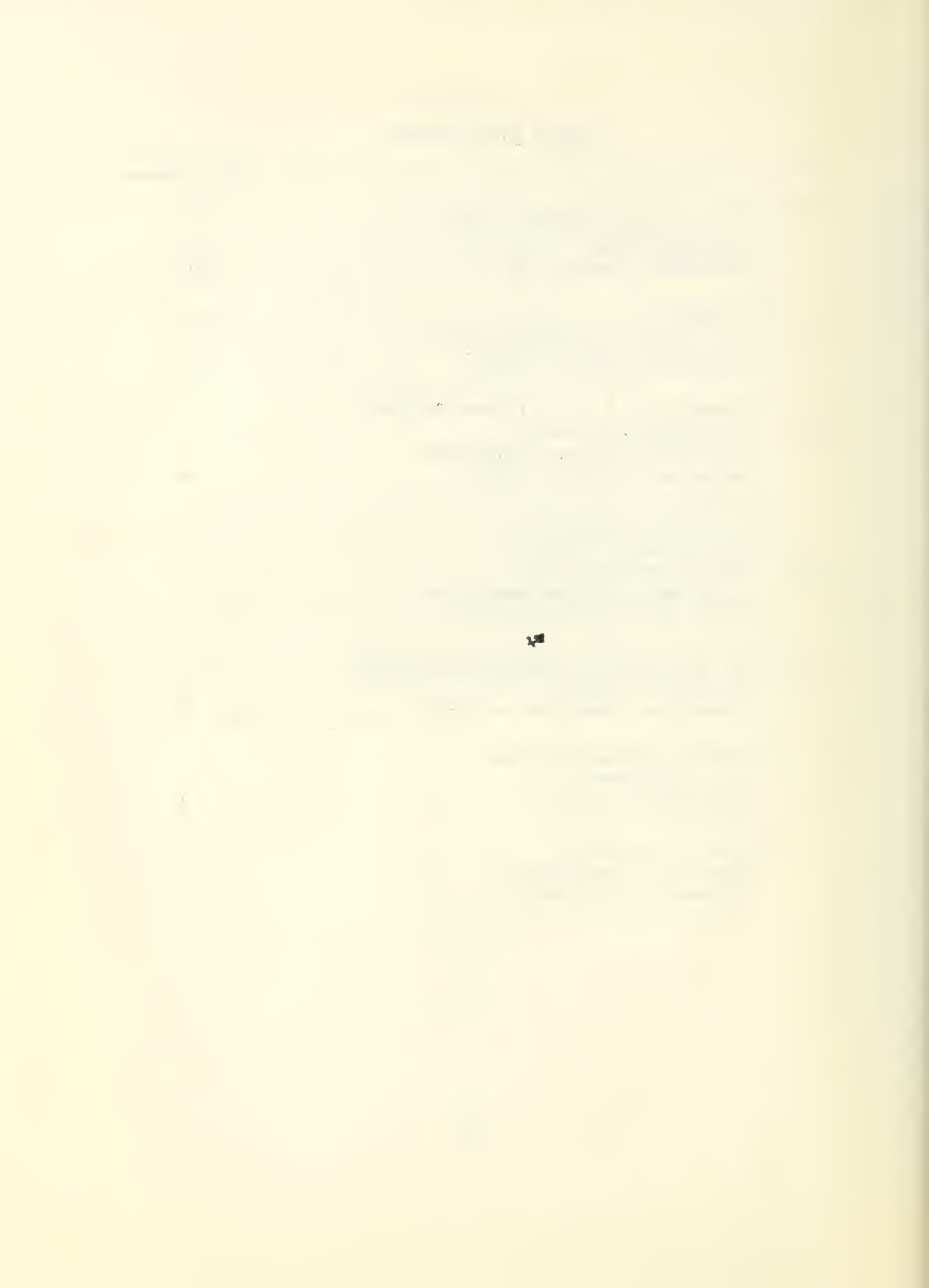
The missile guidance simulation is a transfer function relating  $(\gamma)$  and  $(\sigma)$ . Since the objective of this study is to examine the effect of a digital filter, an arbitrary transfer function was selected which could represent any present day missile. This transfer function contains a time delay due to the radar, a filtering action due to the control (hydraulics etc.), and a second order system representing the missile dynamics.

$$\sigma/\gamma = \frac{A}{S + T_R} \cdot \frac{B}{S + T_C} \cdot \frac{C}{S^2 + DS + E} \quad (A-1)$$

As mentioned above the intention here is to demonstrate the capability of the digital filter in the presence of a large magnitude of noise. The values of the gains and time constants were selected for equation (A-1) after examining several different missile systems which use proportional navigation. Refer to [13] for further elaboration on determining the F and D matrices for a particular system.

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## 13. ABSTRACT

The development of microelectronics has brought into being large capacity digital memories in a small package. In the foreseeable future even more advances can be seen in this trend. Therefore the use of digital computers in control systems will play an even larger role than today.

This work involves a fourth order system to simulate the control and dynamics of a missile. Proportional navigation is used as the guidance method. Studied are the effects of applying different controls which are considered best from a computer study and the effects of applying digital filtering methods. Although these studies were applied to a specific problem, an attempt is made to keep the discussion general in order that the methods may be considered for other problems.

14. KEY WORDS	LINK A		LINK B		LINK C	
	ROLE	WT	ROLE	WT	ROLE	WT
Missile Digital simulation Digital filter Proportional navigation						

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